



Industrial Automation Headquarters

Delta Electronics, Inc.
Taoyuan Technology Center
No.18, Xinglong Rd., Taoyuan City,
Taoyuan County 33068, Taiwan
TEL: 886-3-362-6301 / FAX: 886-3-371-6301

Asia

Delta Electronics (Jiangsu) Ltd.
Wujiang Plant 3
1688 Jiangxing East Road,
Wujiang Economic Development Zone
Wujiang City, Jiang Su Province, P.R.C. 215200
TEL: 86-512-6340-3008 / FAX: 86-769-6340-7290

Delta Greentech (China) Co., Ltd.
238 Min-Xia Road, Pudong District,
ShangHai, P.R.C. 201209
TEL: 86-21-58635678 / FAX: 86-21-58630003

Delta Electronics (Japan), Inc.
Tokyo Office
2-1-14 Minato-ku Shibadaimon,
Tokyo 105-0012, Japan
TEL: 81-3-5733-1111 / FAX: 81-3-5733-1211

Delta Electronics (Korea), Inc.
1511, Byucksan Digital Valley 6-cha, Gasan-dong,
Geumcheon-gu, Seoul, Korea, 153-704
TEL: 82-2-515-5303 / FAX: 82-2-515-5302

Delta Electronics Int'l (S) Pte Ltd.
4 Kaki Bukit Ave 1, #05-05, Singapore 417939
TEL: 65-6747-5155 / FAX: 65-6744-9228

Delta Electronics (India) Pvt. Ltd.
Plot No 43 Sector 35, HSIIDC
Gurgaon, PIN 122001, Haryana, India
TEL : 91-124-4874900 / FAX : 91-124-4874945

Americas

Delta Products Corporation (USA)
Raleigh Office
P.O. Box 12173,5101 Davis Drive,
Research Triangle Park, NC 27709, U.S.A.
TEL: 1-919-767-3800 / FAX: 1-919-767-8080

Delta Greentech (Brasil) S.A.
Sao Paulo Office
Rua Itapeva, 26 - 3º andar Edificio Itapeva One-Bela Vista
01332-000-São Paulo-SP-Brazil
TEL: 55 11 3568-3855 / FAX: 55 11 3568-3865

Europe

Deltronics (The Netherlands) B.V.
Eindhoven Office
De Witbogt 15, 5652 AG Eindhoven, The Netherlands
TEL: 31-40-2592850 / FAX: 31-40-2592851

*We reserve the right to change the information in this manual without prior notice.



ASDA A2-E EtherCAT Interface Servo Drive User Manual

Table of Contents

Chapter 1 ASD-A2-E CoE Drive Overview	1-1
1.1 Communication Specification	1-1
1.2 The Interface of Delta EtherCAT Servo Drive	1-2
1.3 LED Indicators	1-3
1.4 The Topology.....	1-6
1.5 Wiring	1-7
1.5.1 Explanation of I/O (CN1) Connector Signal.....	1-8
1.5.2 CN2 Connector.....	1-9
1.5.3 CN5 Connector (Full-closed Loop)	1-10
1.5.4 CN6 EtherCAT Terminal	1-11
1.5.5 CN7 Extension DI.....	1-12
1.5.6 CN-STO.....	1-13
1.5.7 STO with Safety Relay	1-14
1.5.8 STO Disable	1-14
1.6 Dimension.....	1-15
1.6.1 220V Series.....	1-15
1.6.2 400V Series.....	1-17
Chapter 2 System Setup	2-1
2.1 Parameter Settings of EtherCAT Mode	2-1
2.2 TwinCAT Setup.....	2-4
2.3 Synchronization Modes Setting	2-12

2.3.1	Two Synchronization Modes of Delta Servo.....	2-12
2.3.2	Select the Synchronization Mode	2-13
2.3.3	Synchronous Clock Time Setting	2-13
2.4	PDO Mapping	2-15
2.4.1	Default PDO Mappings.....	2-15
2.4.2	Re-define a PDO Mapping	2-16
2.4.3	Using TwinCAT	2-17
Chapter 3 EtherCAT Communication States.....		3-1
3.1	State Transition Operation.....	3-2
Chapter 4 EtherCAT Troubleshooting		4-1
Chapter 5 CANopen Operation Mode.....		5-1
5.1	Profile Position Mode	5-1
5.1.1	Description	5-1
5.1.2	Operation Procedures	5-1
5.1.3	Advanced Setting Procedures	5-2
5.1.4	Associated Object List.....	5-3
5.2	Interpolation Position Mode	5-4
5.2.1	Description	5-4
5.2.2	Operation Procedures	5-5
5.2.3	Associated Object List.....	5-5
5.3	Cyclic Synchronous Position Mode.....	5-6
5.3.1	Description	5-6

5.3.2 The Function of CSP Mode	5-6
5.3.3 Operation Procedures	5-6
5.3.4 Associated Object List.....	5-7
5.4 Homing Mode	5-8
5.4.1 Description	5-8
5.4.2 Operation Procedures	5-8
5.4.3 Associated Object List.....	5-9
5.5 Profile Velocity Mode	5-10
5.5.1 Description	5-10
5.5.2 Operation Procedures	5-10
5.5.3 Advanced Setting Procedures.....	5-11
5.5.4 Associated Object List.....	5-11
5.6 Cyclic Synchronous Velocity Mode.....	5-12
5.6.1 Description	5-12
5.6.2 The Function of CSV Mode	5-12
5.6.3 Operation Procedures	5-12
5.6.4 Associated Object List.....	5-13
5.7 Profile Torque Mode	5-14
5.7.1 Description	5-14
5.7.2 Operation Procedures	5-14
5.7.3 Advanced Setting Procedures.....	5-14
5.7.4 Associated Object List.....	5-15
5.8 Cyclic Synchronous Torque Mode	5-16
5.8.1 Description	5-16
5.8.2 The Function of CST Mode	5-16

5.8.3 Operation Procedures	5-16
5.8.4 Associated Object List.....	5-17
5.9 Limit Position Handling Procedure.....	5-18
5.9.1 Description	5-18
5.9.2 Operation Procedures	5-18
5.10 Touch Probe Function	5-19
5.10.1 Description	5-19
5.10.2 Touch Probe Function	5-19
5.10.3 Touch Probe Status.....	5-20
5.10.4 Associated Object List.....	5-21
Chapter 6 Object Dictionary Entries	6-1
6.1 Specifications for Objects	6-1
6.1.1 Object Type	6-1
6.1.2 Data Type.....	6-1
6.2 Overview of Object Group 1000 _h	6-2
6.3 Overview of Object Group 6000 _h	6-3
6.4 Details of Objects.....	6-6
Chapter 7 Alarm List.....	7-1
7.1 EtherCAT Communication Fault Messages	7-1
7.2 Error Code Table	7-5
7.3 SDO Error Message Abort Codes.....	7-8
Chapter 8 Reference.....	8-1

Chapter 1 CoE Drive Overview

1.1 Communication Specification

EtherCAT Communication	Physical layer	100BASE-TX
	Communication connector	RJ45 × 2 (Connector CN6A=IN, CN6B=OUT)
	Network topology	Line connection
	Baud rate	2 × 100 Mbps (full duplex)
	Frame data length	Maximum 1484 bytes
	SyncManager	SM0: Mailbox output SM1: Mailbox input SM2: Process data output SM3: Process data input
	FMMU (Fieldbus Memory Management Units)	FMMU0: Process data output area FMMU1: Process data input area FMMU2: Mailbox status area
	Device profile	CoE: CANopen over EtherCAT
	Synchronization mode	DC synchronization (SYNC0) Non- synchronized (Free Run)
	Communication object	SDO: Service Data Object PDO: Process Data Object EMCY: Emergency Data Object
	LED indicator (On RJ45 Connector)	EtherCAT ERR (ER) × 1 EtherCAT Link/Activity (L/A) × 2 EtherCAT RUN (RN) × 1
Application layer specifications		IEC61800-7 CiA402 Drive Profile
The supported CiA402 operation modes		<ul style="list-style-type: none">■ Profile Position Mode (PP)■ Profile Velocity Mode (PV)■ Profile Torque Mode (PT)■ Homing Mode (HM)■ Interpolated Position Mode(IP)■ Cycle Synchronized Position Mode (CSP)■ Cycle Synchronized Velocity Mode (CSV)■ Cycle Synchronized Torque Mode (CST)

1.2 The Interface of Delta EtherCAT Servo Drive

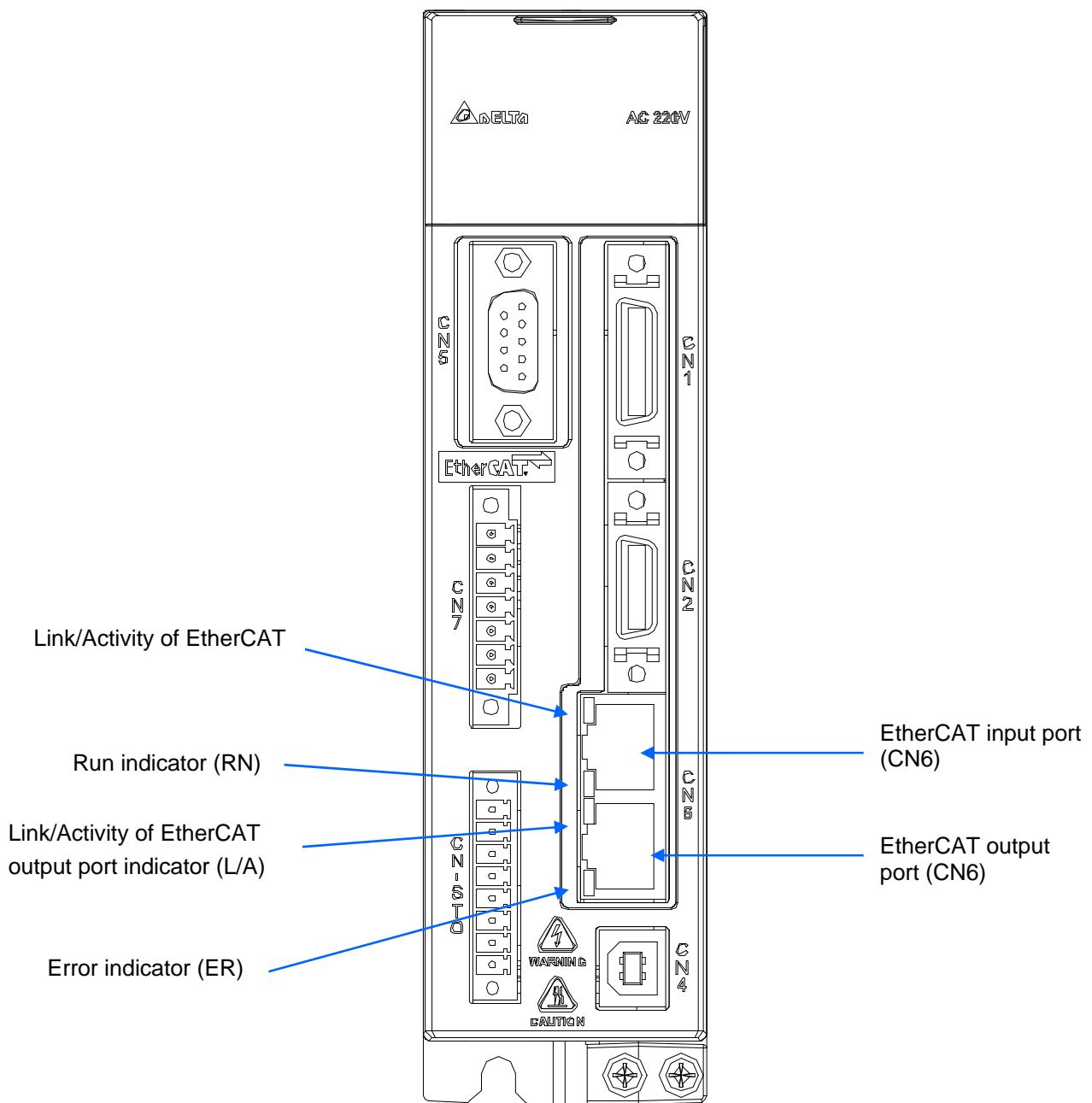


Figure 1. The Interface of Delta EtherCAT Servo Drive

EtherCAT® is registered trademark and patented technology, licensed by Beckhoff Automation GmbH, Germany.

1.3 LED Indicators

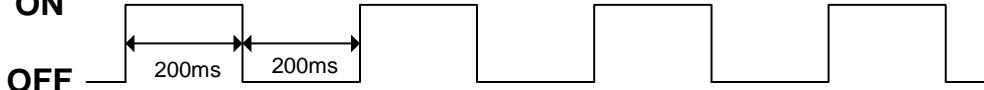
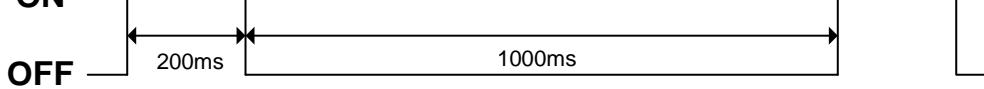
Indicator state	Indicator pattern
ON	ON ————— OFF
Blinking	ON  OFF
Single Flash	ON  OFF
OFF	ON OFF —————

Figure 2. RJ45 LED indicator pattern

■ ERROR (ER) LED

The ER LED indicator shows the error status of EtherCAT communication.

Indicator state	Slave State
Off	No error
Blinking	State change error
Single Flash	Synchronization error SyncManager error
On	PDI Watchdog timeout

State change error:	The state machine does not allow the system to change its state because the wrong parameter settings. Please refer to Figure 29 for its switching conditions.
Synchronization error:	The synchronization of Master Clock and Slave Clock is failed.
SyncManager error:	The data of process data is lost when receiving.
PDI Watchdog timeout:	The hardware failure on slave. Please contact Delta distributors for assistance.

■ RUN LED

The RUN LED indicator shows the status of EtherCAT state machine

Indicator state	Slave State
Off	INIT
Blinking	PRE-OPERATIONAL
Single Flash	SAFE-OPERATIONAL
On	OPERATIONAL

INIT:	After power on, the EtherCAT slave will get into INIT state if there is no error. At INIT state, no communication servo is provided. Accessing slave's register from the host is available at this state.
PRE-OPERATIONAL:	The Mailbox can be used to communicate with its host controller.
SAFE-OPERATIONAL:	Both SDO and TxPDO, which can send cyclic data from the slave to the host, are workable.
OPERATIONAL:	SDO, TxPDO and RxPDO are working.

- Link Activity (L/A) LED

The L/A LED indicator shows the physical link status and the link activity.

Indicator state	Slave State
Off	No link
Blinking	Link and activity
On	Link without activity

No link:	The link has not established yet.
Link and activity:	The data is exchanging with its partners.
Link without activity:	The link is established but no data is exchanging now.

1.4 The Topology

The topology is defined by the host controller. Please refer to the host controller's application manual. There are only one input port and one output port on Delta servo drive for EtherCAT communication ports.

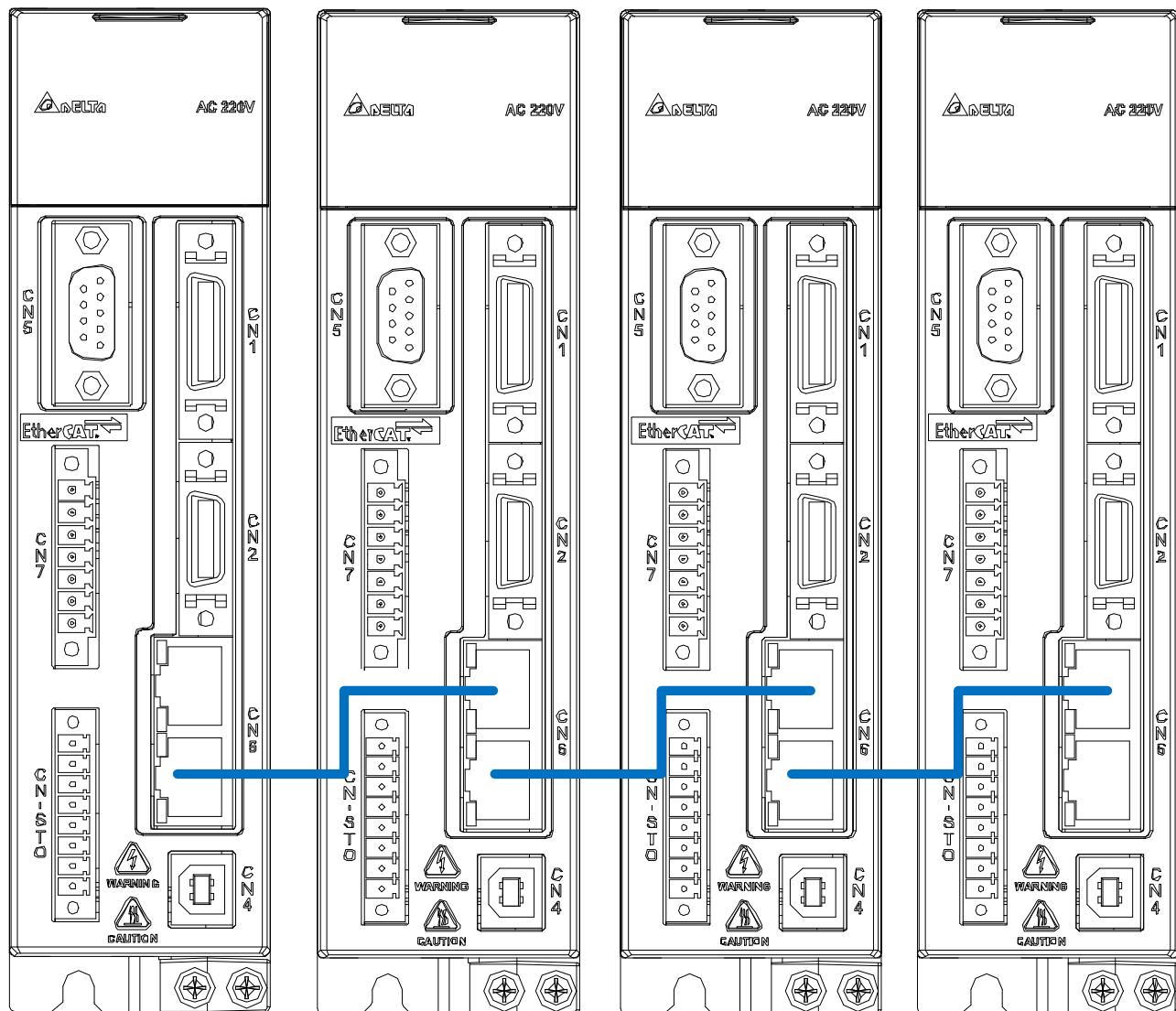


Figure 3. EtherCAT connection topology example

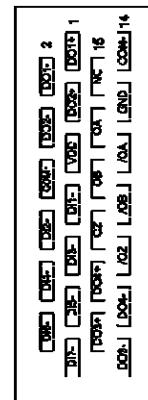
1.5 Wiring

I/O Signal (CN1) Connection and Connector Terminal Layout

In order to have a more flexible communication with the master, 4 programmable Digital Output (DO) and 7 programmable Digital Input (DI) are provided, which are parameter P2-18~P2-21 and P2-10~P2-16 respectively. In addition, the differential output encoder signal A+, A-, B+, B-, Z+ and Z- is also provided. The followings are the pin diagrams.



CN1 Connector (female)

CN1 Connector (male)
rear view

2	DO1-	Digital output	1	DO1+	Digital output	14	COM-	VDD power ground
4	DO2-	Digital output	3	DO2+	Digital output	15	NC	N/A
6	COM+	Power input (12~24V)	5	VDD	+24V Power output	17	OA	Encoder/ A pulse output
8	DI2-	Digital input	7	DI1-	Digital input	19	OB	Encoder/ B pulse output
10	DI4-	Digital input	9	DI3-	Digital input	21	OZ	Encoder/ Z pulse output
12	DI6-	Digital input	11	DI5-	Digital input	23	DO4+	Digital output
			13	DI7-	Digital input	25	DO3+	Digital output
						24	DO4-	Digital output
						26	DO3-	Digital output



NC means NO CONNECTION. This terminal is for internal use only. Do not connect it, or it may damage the servo drive.

1.5.1 Explanation of I/O (CN1) Connector Signal

The following details the signals listed in previous section.

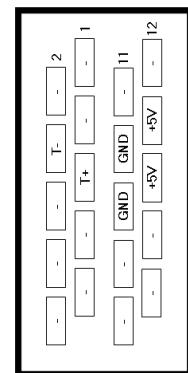
General Signals

Signal Name		Pin No	Function	Wiring Method (Refer to 3.4.3)
Position pulse (output)	OA	17	Encoder signal output A, B, Z (Line Driver output)	C13/C14
	/OA	18		
	OB	19		
	/OB	20		
	OZ	21		
Power	/OZ	22		
	VDD	5	VDD is the +24V power provided by the drive and is for Digital Input (DI) and Digital Output (DO) signal. The maximum current is 500mA.	-
	COM+	6	COM+ is the common input of Digital Input (DI) and Digital Output (DO) voltage. When using VDD, VDD should be connected to COM+. If not using, it needs to apply the external power (+12V ~+24V). Its positive end should connect to COM+ and the negative end should connect to COM-.	
	COM-	14		
Other	GND	16	VCC voltage is based on GND.	
	NC	15	NO CONNECTION. This terminal is for internal use only. Do not connect it, or it may damage the servo drive.	

1.5.2 CN2 Connector

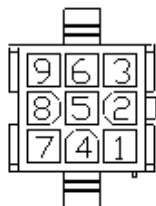
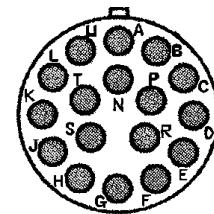
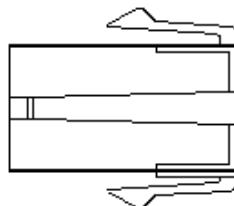


CN2 Connector (female)



CN2 Connector (male)

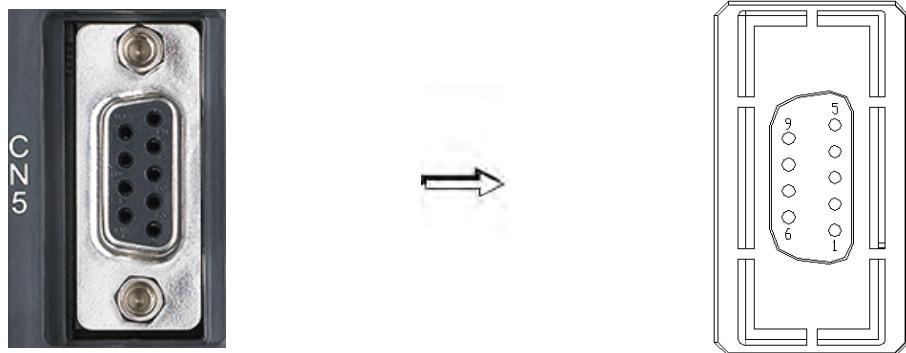
Rear view

Quick Connector
HOUSING: AMP (1-172161-9)Military Connector
3106A-20-29S

Drive Connector			Motor Connector		
Pin No	Terminal Symbol	Function and Description	Military connector	Quick connector	Color
5	T+	Serial communication signal input / output (+)	A	1	Blue
4	T-	Serial communication signal input / output (-)	B	4	Blue & Black
-	-	Reserved	-	-	-
-	-	Reserved	-	-	-
14,16	+5V	Power +5V	S	7	Red/Red & white
13,15	GND	Power ground	R	8	Black/Black & white
-	-	shielding	L	9	-

1.5.3 CN5 Connector (Full-closed Loop)

Connect linear scale or encoder (A, B, Z format) to the servo and form a full-closed loop. In position mode, the pulse command issued by the controller is based on the control loop of the external linear scale. Please refer to Chapter 6.



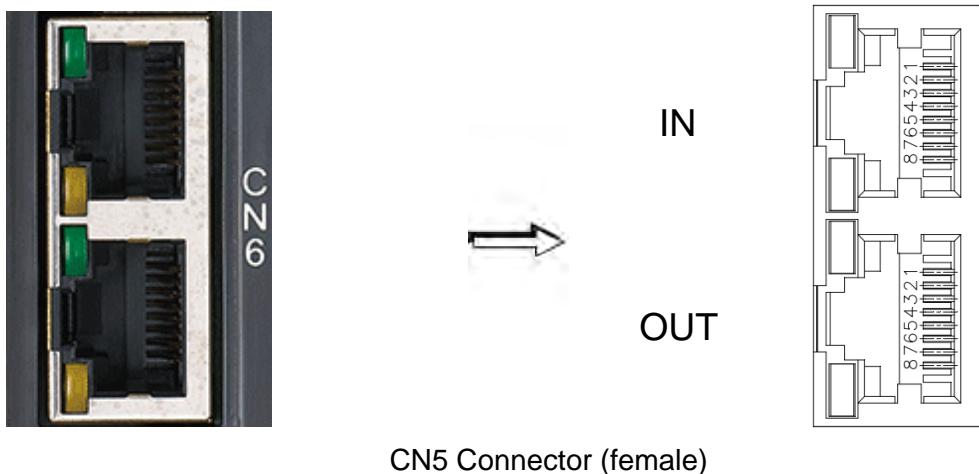
CN5 Connector (female)

Pin No	Signal Name	Terminal Symbol	Function and Description
1	/Z phase input	Opt_Z	/Z phase
2	/B phase input	Opt_B	/B phase
3	B phase input	Opt_B	B phase
4	A phase input	Opt_A	A phase
5	/A phase input	Opt_A	/A phase
6	Encoder grounding	GND	Ground
7	Encoder grounding	GND	Ground
8	Encoder power	+5V	+ 5V power
9	Z phase input	Opt_Z	Z phase



1. It only supports the encoder of AB phase and 5V voltage.
2. The application of full-closed loop: it supports the encoder of highest resolution 1280000 pulse/rev (A pulse number per motor revolution for a full-closed loop that corresponds to an optical signal with AB (Quadrature) phase pulses (4x).).

1.5.4 CN6 EtherCAT Terminal



CN5 Connector (female)

Pin No	Signal Name	Terminal Symbol	Function and Description
1	TX +	TX +	Transmit +
2	TX -	TX -	Transmit -
3	RX +	RX +	Receive +
4	-	-	-
5	-	-	-
6	RX -	RX -	Receive -
7	-	-	-
8	-	-	-



1. The maximum distance between two stations should be 50 meters.
2. Please use CAT5e STP Shielding.

1.5.5 CN7 Extension DI



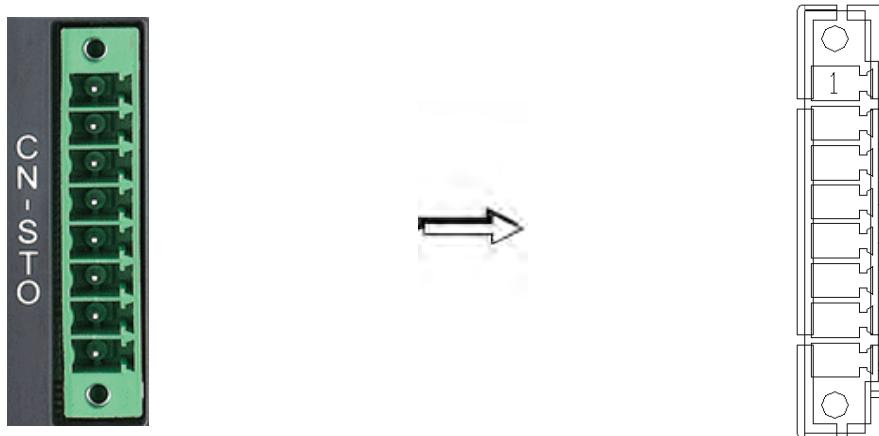
CN7 Connector (male)

Pin No	Signal Name	Terminal Symbol	Function and Description
*1	VDD 24V power	COM+	VDD (24V) power is the same as the voltage of Pin11 in CN1
2	Extension DI9	EDI 9-	Digital input pin 9-
3	Extension DI10	EDI 10-	Digital input pin 10-
4	Extension DI11	EDI 11-	Digital input pin 11-
5	Extension DI12	EDI 12-	Digital input pin 12-
6	Extension DI13	EDI 13-	Digital input pin 13-
7	Extension DI14	EDI 14-	Digital input pin 14-



➤ **Caution: Do not apply to dual power or it may damage the servo drive.**

1.5.6 CN-STO



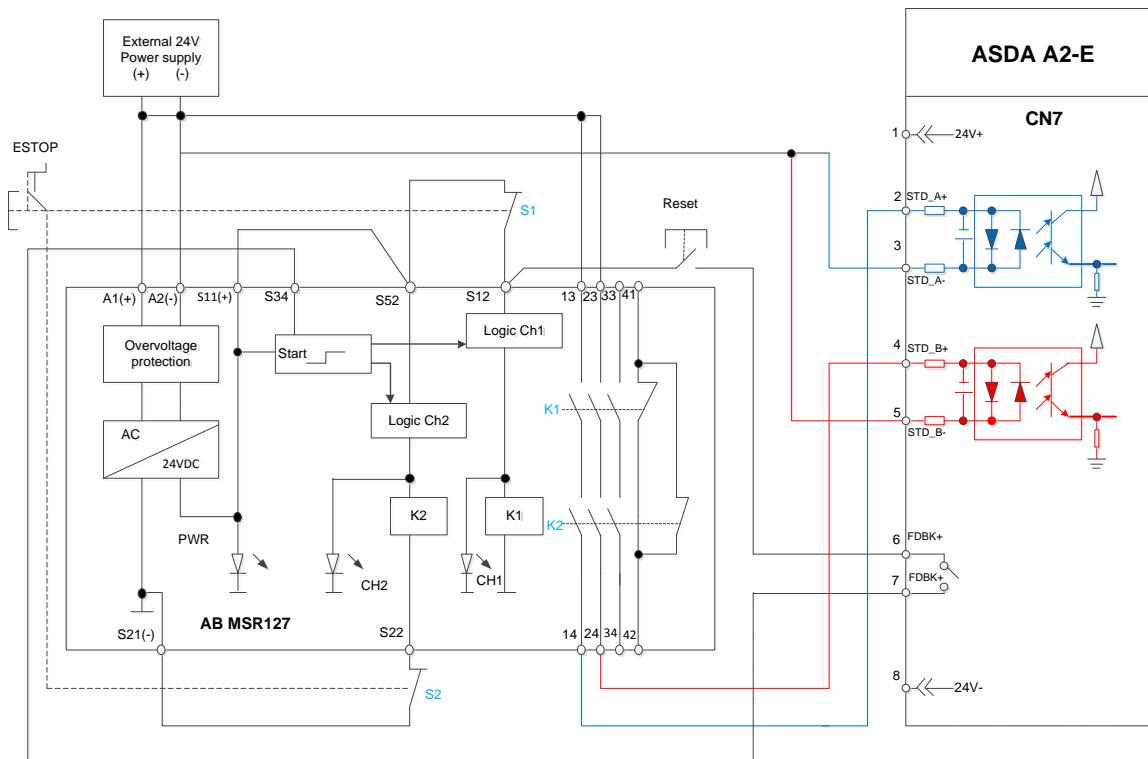
CN-STO Connector (male)

Pin No	Signal Name	Terminal Symbol	Function and Description
*1	VDD24V power	COM+	VDD (24V) power is the same as the voltage of Pin11 in CN1
2	STO_A	STO_A	STO input pin A+
3	/STO_A	/STO_A	STO input pin A-
4	STO_B	STO_B	STO input pin B+
5	/STO_B	/STO_B	STO input pin B-
6	FDBK_A	FDBK_A	STO alarm output pin A, Relay Output Max. Current : 1A
7	FDBK_B	FDBK_B	STO alarm output pin B, Relay Output Max. Current : 1A
8	COM-	COM-	VDD(24V) power ground

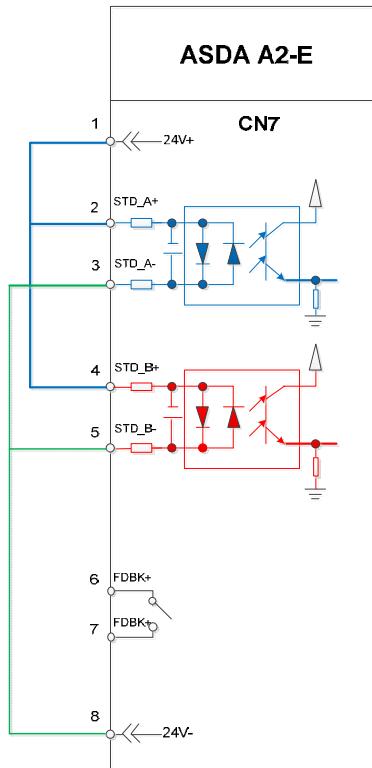


➤ **Caution: Do not apply to dual power or it may damage the servo drive.**

1.5.7 STO with Safety Relay



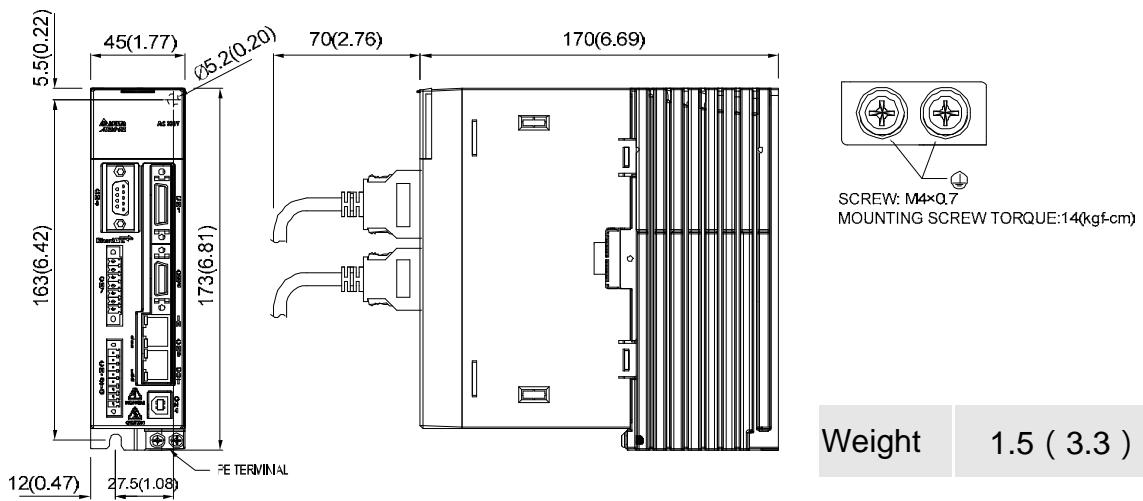
1.5.8 STO Disable



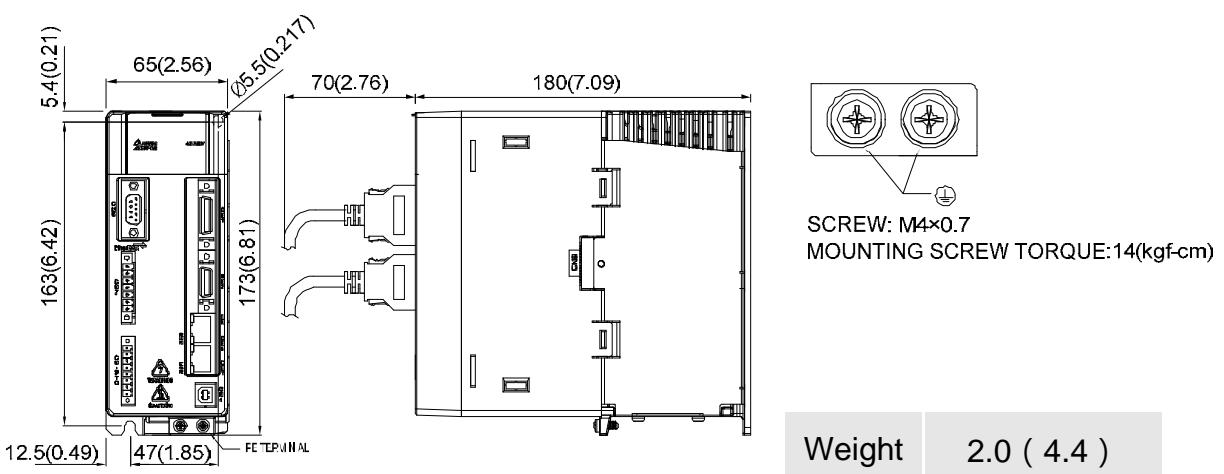
1.6 Dimension

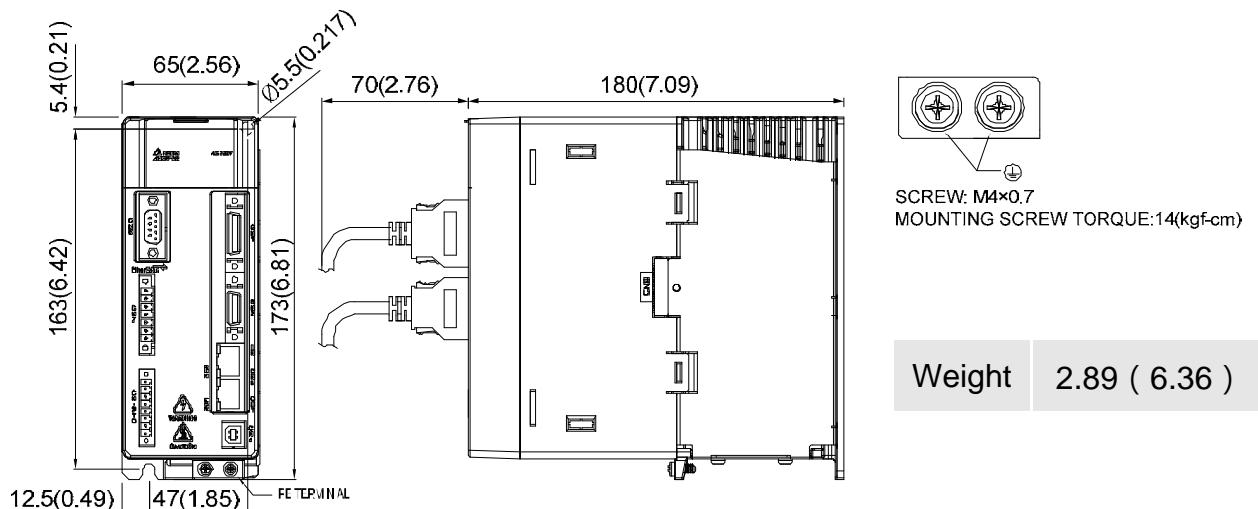
1.6.1 220V Series

100W/200W/400W



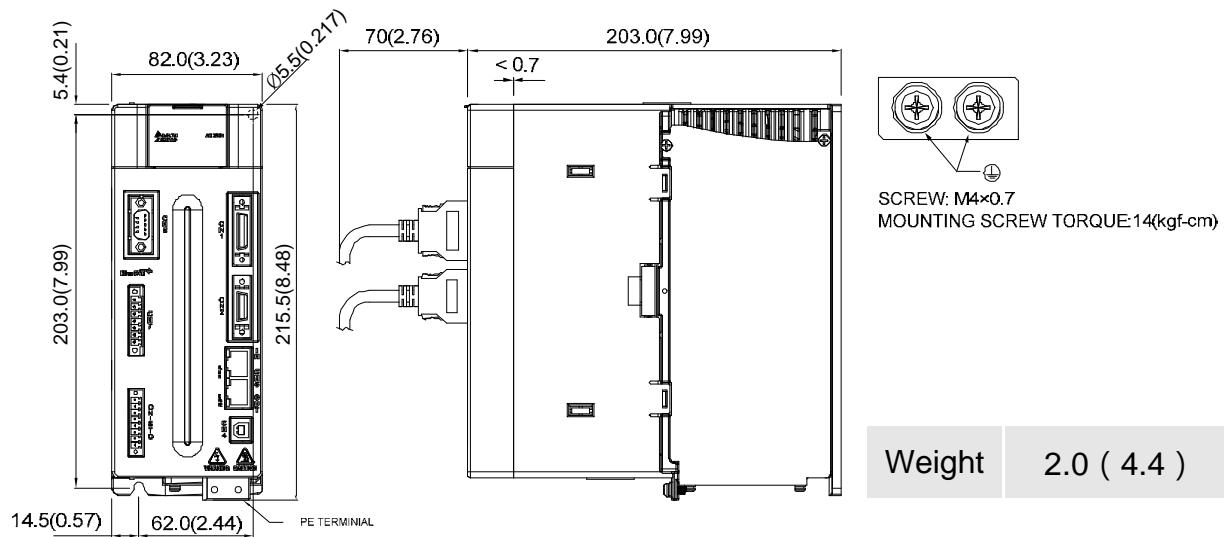
750W/1kW/1.5kW



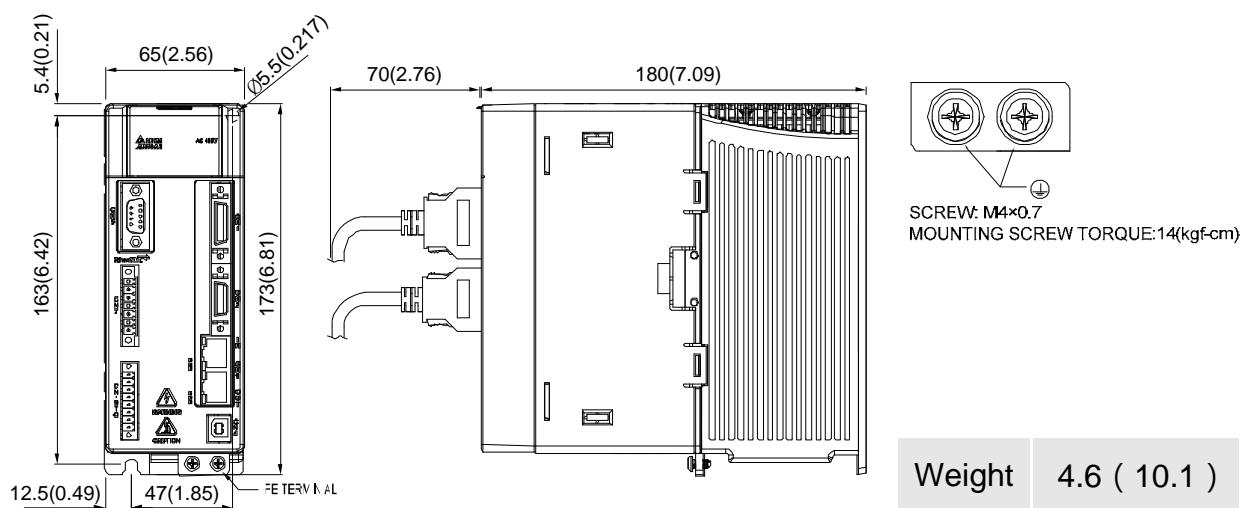
2kW/3kW

1.6.2 400V Series

400W/750W/1kW/1.5kW



2kW/3kW/4.5kW/5.5kW





1. Dimensions are in millimeters (inches); Weights are in kilograms (kg) and pounds (lbs).
2. Dimensions and weights of the servo drive may be revised without prior notice.

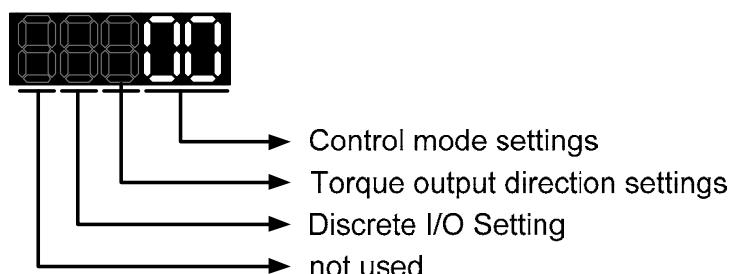
Chapter 2 System Setup

2.1 Parameter Settings of EtherCAT Mode

1. Set parameter **P1-01** to **0x0C_h** for EtherCAT communication and CANopen as the application layer.
2. Restart the system of servo drive.

P1 - 01•	CTL	Control Mode and Output Direction	Address: 0102H, 0103H
Operation Interface:	Keypad / Software	Communication	Related Section: Section 8.1, Table A
Default:	0		
Control Mode:	ALL		
Unit:	pulse (P mode), r/min (S mode), N·m (T mode)		
Range:	00 ~ 0x110F		
Data Size:	16-bit		
Display Format:	Hexadecimal		

Settings:



Control mode settings

	PT	PR	S	T	Sz	Tz
Single Mode						
00	▲					
01		▲				
02			▲			
03				▲		
04					▲	
05						▲
Multiple Mode						
0E	▲	▲	▲			
0F	▲	▲		▲		

	PT	PR	S	T	Sz	Tz
Dual Mode						
06	▲			▲		
07	▲				▲	
08		▲	▲			
09		▲			▲	
0A			▲	▲		
0B	N/A					
0C	CANopen Mode					
0D	▲	▲				

PT: Position control mode. The command is from the external pulse or analog voltage (External analog voltage will be available soon).
 Execution of the command selection is via DI.PTAS.)

PR: Position control mode. The command is from the internal signal.
 Execution of 64 positions is via DI.POS0 ~ POS5. A variety of homing control is also provided.

S: Speed control mode. The command is from the external signal or internal signal. Execution of the command selection is via DI.SPD0 and DI.SPD1.

T: Torque control mode. The command is from the external signal or internal signal. Execution of the command selection is via DI.TCM0 and DI.TCM1.

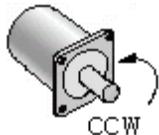
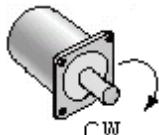
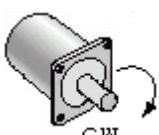
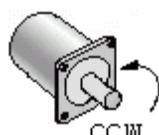
Sz: Zero speed / internal speed command

Tz: Zero torque / internal torque command

Dual Mode: The control mode selection is via DI signals. For example, either PT or S control mode can be selected via DI signal, S-P (see Table A).

Multiple Mode: The control mode selection is via DI signals. For example, PT, PR or S control mode can be selected via DI signals, S-P and PT-PR (see Table A).

Torque output direction settings

Direction	0	1
Forward		
Reverse		

Discrete I/O Setting

- 1: When switching to different mode, digital inputs/outputs (P2-10 ~ P2-22) will be set to the default value according to the mode you selected.
- 0: When switching to different mode, the setting value of digital inputs/outputs (P2-10 ~ P2-22) will remain the same and will not be changed.

2.2 TwinCAT Setup

A lot of software can be applied to configure EtherCAT system. The following procedures are the example of TwinCAT of Beckhoff. Please install the software properly before you start to configure the system.

1. Copy Delta XML description to the folder the TwinCAT installed (usually C:\TwinCAT\Io\EtherCAT).
2. Restart the TwinCAT.
3. The configuration procedure can be started by applying TwinCAT manager which shown as below.

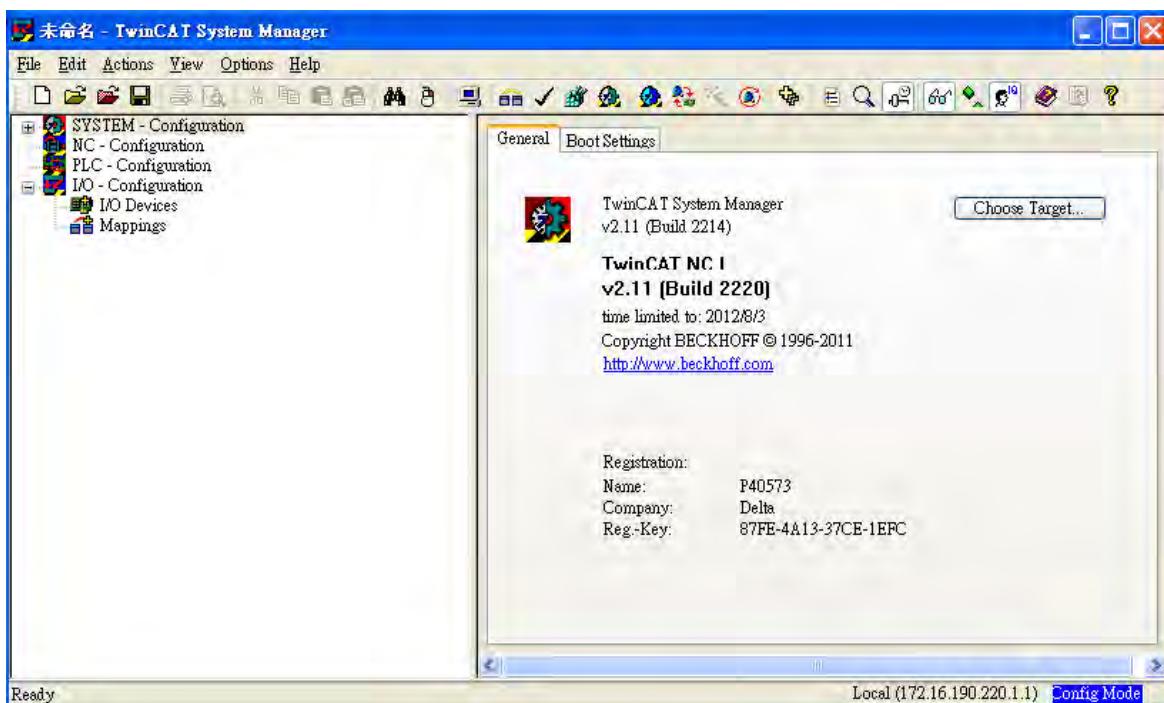


Figure 4

4. Install the Network Interface Card (NIC) for EtherCAT communication.
 - Select Options → Show Real Time Ethernet Compatible Devices.

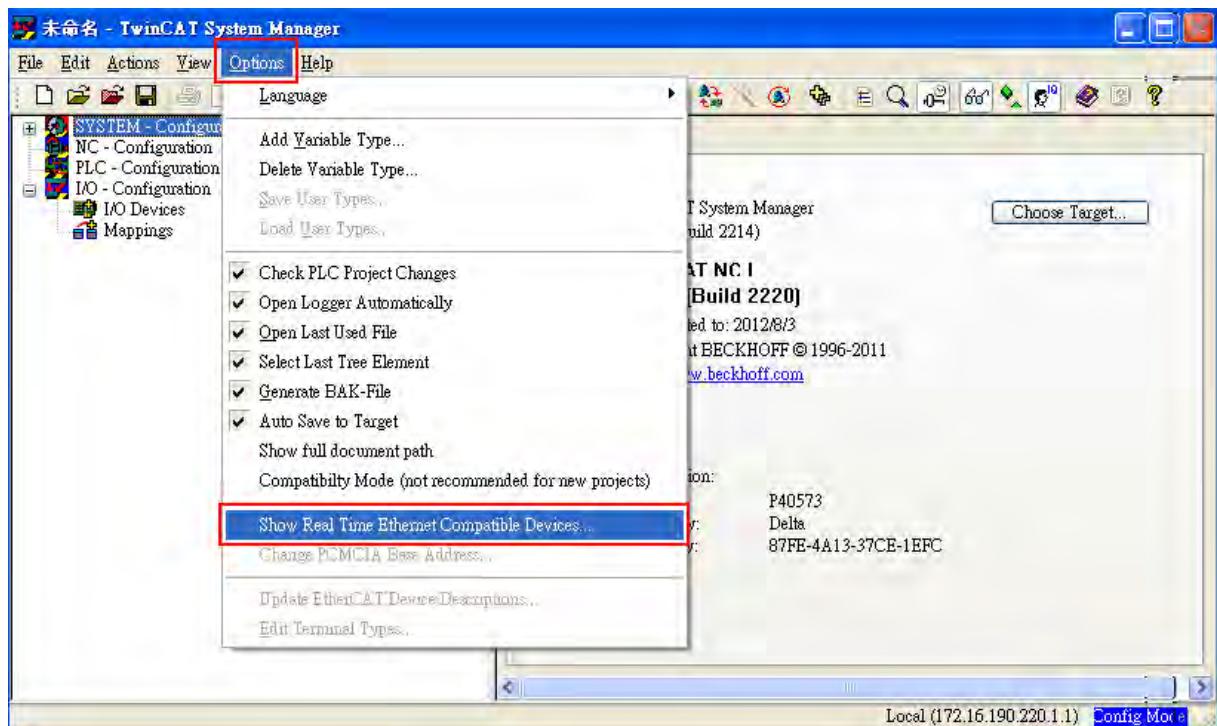


Figure 5

- Select the correct Adapter from the devices (NICs) installed in the computer for EtherCAT communication and click “Install”.

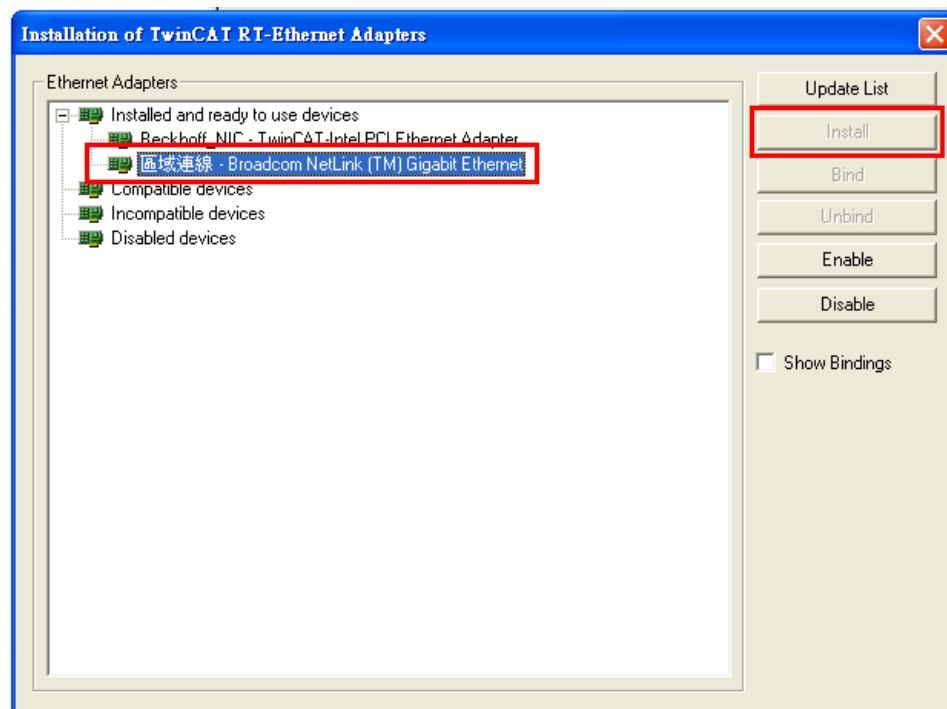


Figure 6

5. Open a new project from the drop down menu File → new.
6. Right click I/O Devices and select **Scan Devices** or Press <F5> to scan the devices. Click **OK** in the pop-up dialog window to confirm the information.

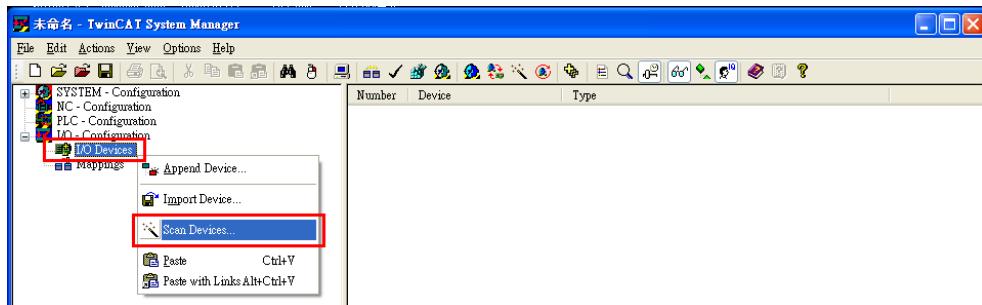


Figure 7



Figure 8

7. Find Device [n] (EtherCAT), select this device and click **OK**.

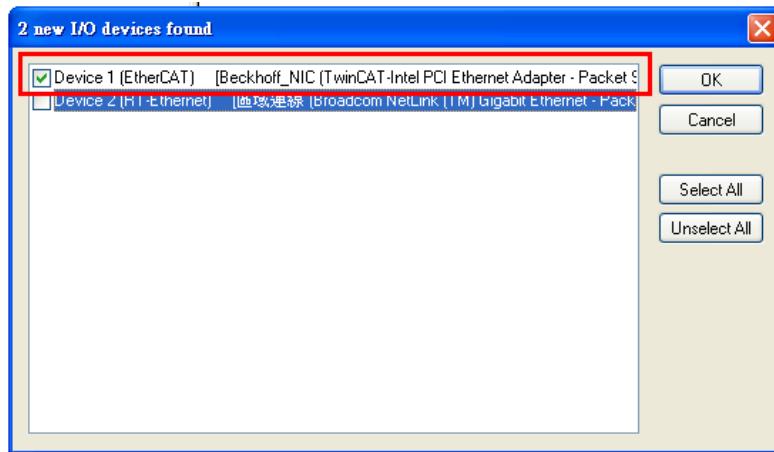


Figure 9

8. Click **Yes** to scan for boxes.

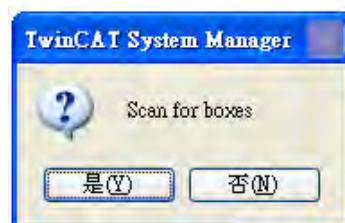


Figure 10

9. Click **Yes** to Add drives to NC-Configuration.



Figure 11

10. Click **No** and TwinCAT will be switched to **Config mode**.



Figure 12

11. TwincAT is in Config Mode. In the left panel, it shows **Device (EtherCAT)** and you can find ASDA A2-E CoE Drive.

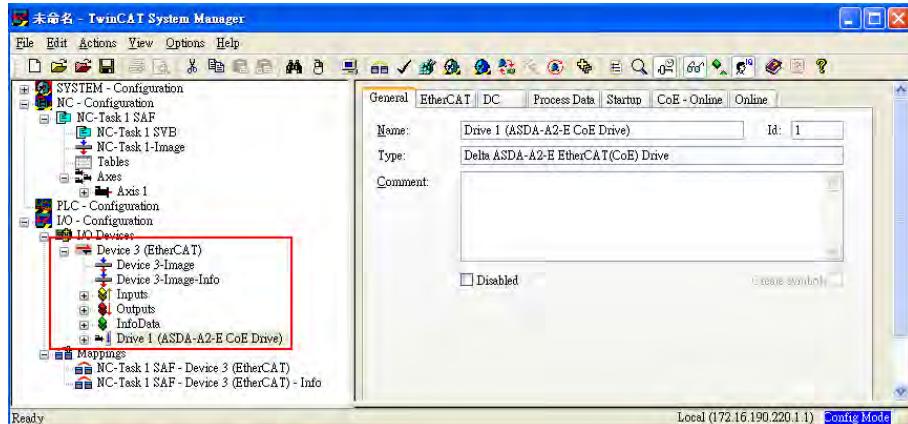


Figure 13

12. Select the Drive (ASDA A2-E) and in **Online** tab you can check if the device's EtherCAT state machine (ESM) is in PREOP state.

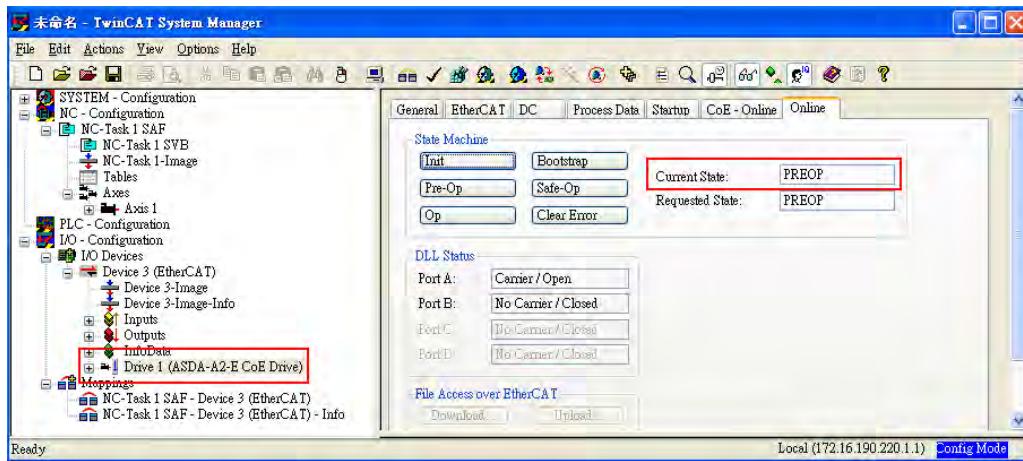


Figure 14

13. Double click on Drive (ASDA A2-E CoE Drive) and it will show:

2nd TxPDO – **CoE Tx PDO mapping**
 3rd RxPDO – **CoE Rx PDO mapping**
WcState
InfoData

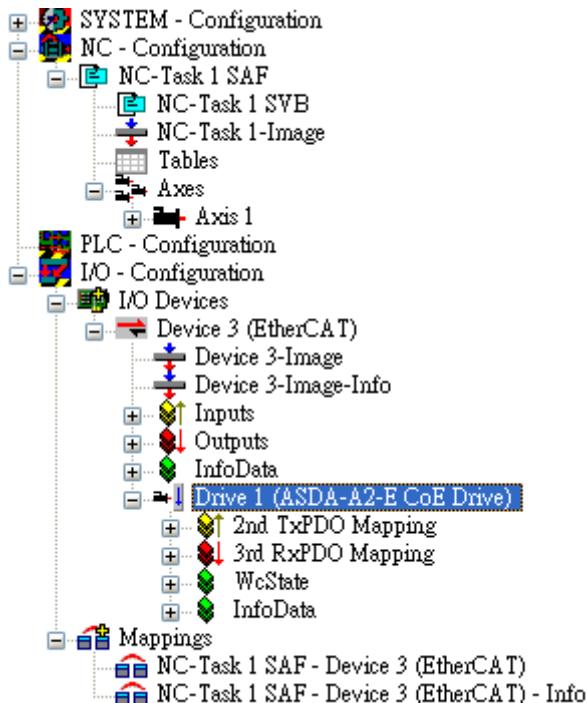


Figure 15

14. Set the communication cycle* and the default value is 2ms.

- Select **NC-Task 1 SAF** in the left window, and set **Cycle ticks** as communication cycle (The minimum value is 1ms) in the right window.

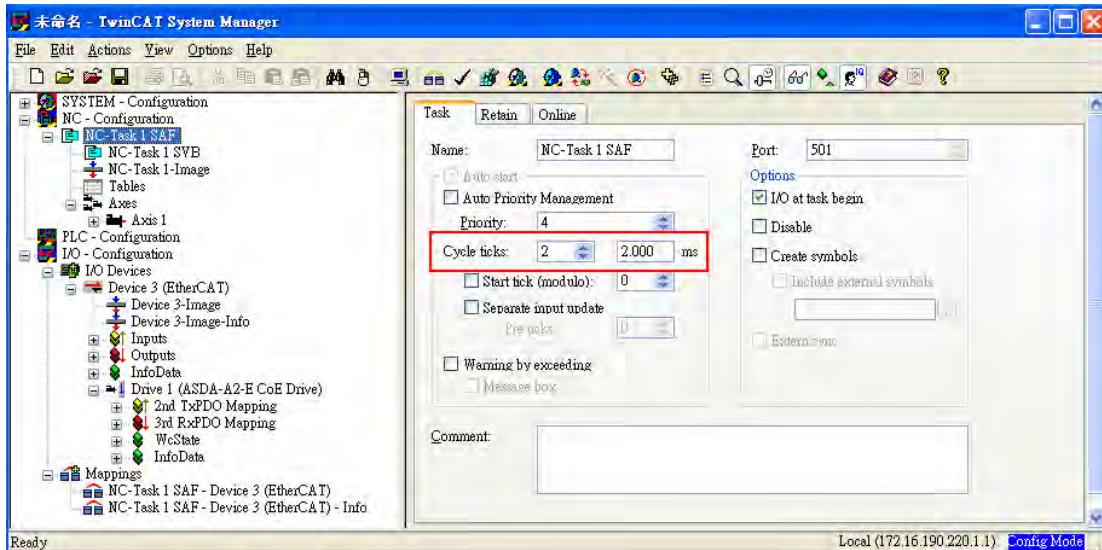


Figure 16

*The communication cycle time, SYNC0 cycle time, and PDO cycle time should be set to the same value.

15. Set **Following Error Calculation** to **Extern**.

- Select **Axis 1_Drive** in the left window → In parameter column of the right window, select **Extern** in **Following Error Calculation** → click **Download** and then click **OK** in pop-up dialog.

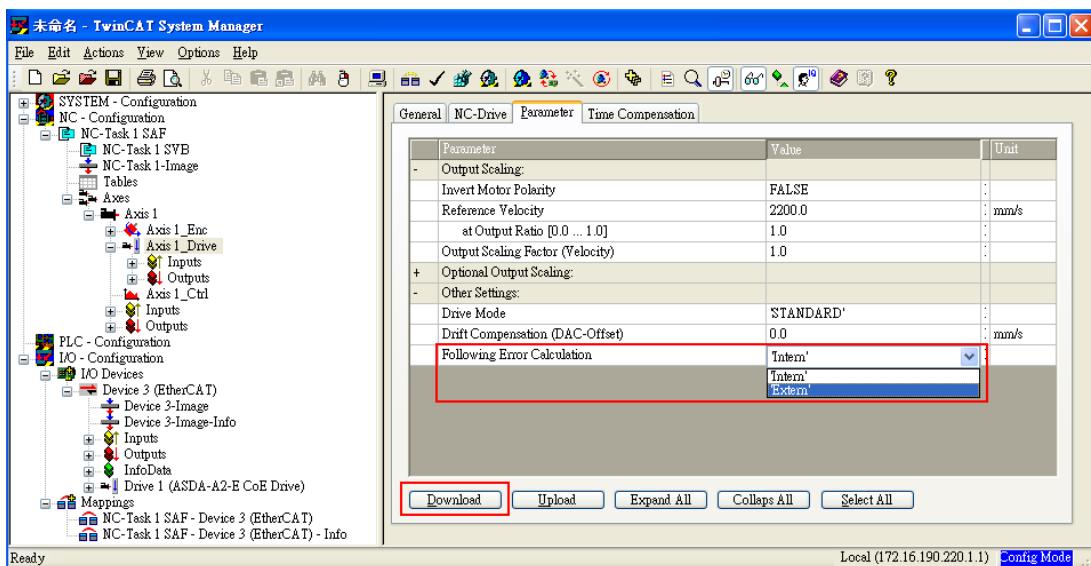


Figure 17

16. Switch TwinCAT to Run Mode.

- Press  to generate Mappings → press  to check configuration → and press  to activate configuration. TwinCAT will be switched to Run Mode and then click OK in pop-up dialog.



Figure 18

17. Enable the axis (Servo On).

- Under NC-Configuration of the left window, select **Axis 1** → select **Online** tab in the right window → click **Set**.

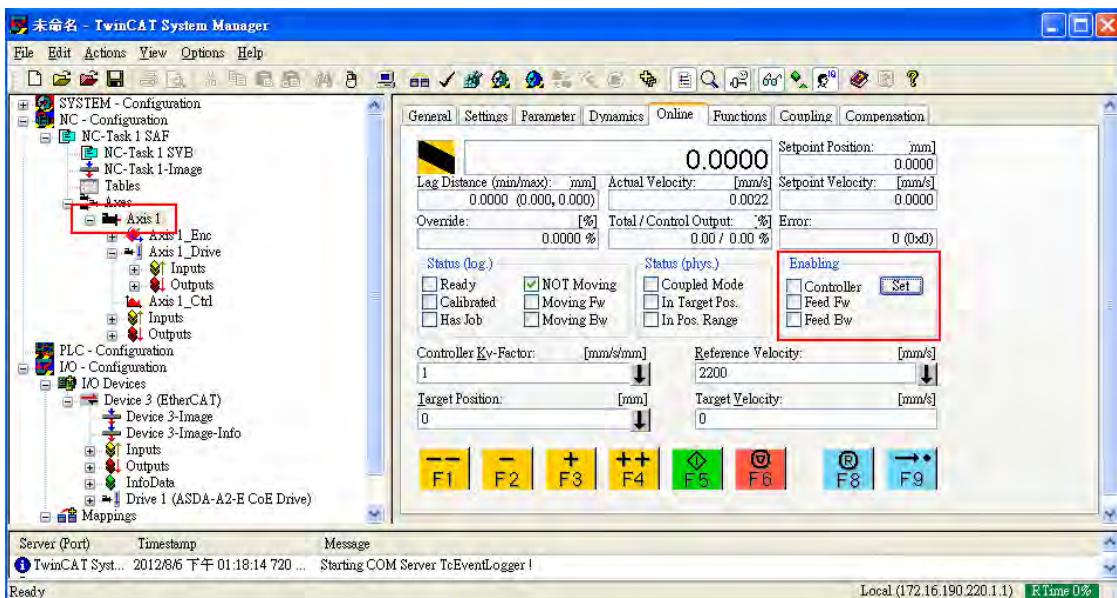


Figure 19

- In pop-up dialog, click **All** to enable the motor.

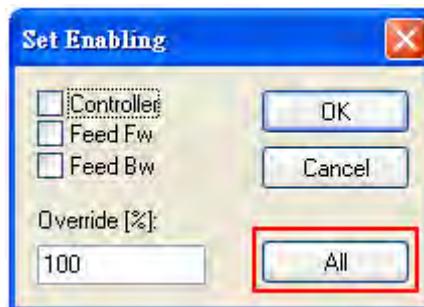


Figure 20

18. In **Online** tab, there are two different speed levels of jogging buttons for forward and backward movement which can test the system. During the operation, please **Be Ensured** that the movement would not damage your system and endanger the personnel safety.



Figure 21

2.3 Synchronization Modes Setting

2.3.1 Two Synchronization Modes of Delta Servo

ASDA A2-E supports two synchronization modes, Free Run mode and DC-Synchronous mode. Please note that the asynchronous Free Run mode is still under the definition of “Synchronization Modes” within EtherCAT specification guide.

■ Free Run Mode (Asynchronous)

The master and slaves are running in an asynchronous manner. The master and the slave both have their own clock to calculate the time. In other words, there is no synchronous clock between the master and the slave. A command sent by the master and a reply from the slave only consists with a sequential order instead of strict clock timing. For example, a master sends a PDO at tick t1 and the slave will receive it at tick t1 or tick t2 and vice versa.

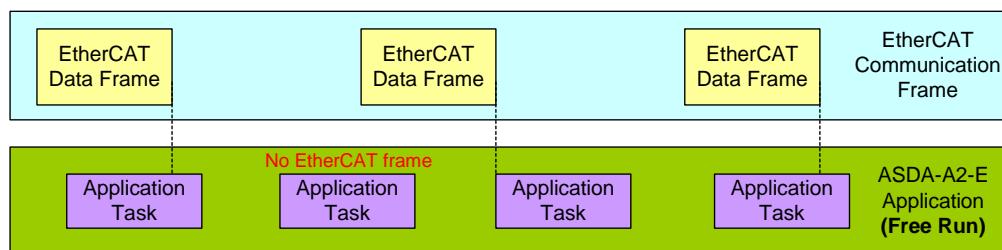


Figure 22. Free Run Mode synchronization

■ DC-Synchronous Mode (SYNC0 synchronization)

There exists a clock tick for the master and all slaves operation. A data sent by the master will be received by slave(s) at the same clock interval. The master will inform all slaves about its clock and ask slaves to align according to the time. A strict clock tick is always running within this system.

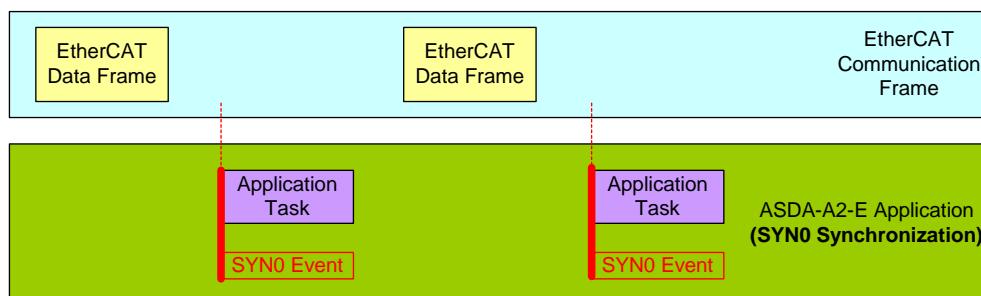


Figure 23. DC-Synchronous mode synchronization

2.3.2 Select the Synchronization Mode

1. Select Drive (ASDA A2-E CoE Drive) in the left window.
2. The DC tab in the right window, users can select DC-Synchronous or Free Run as the Operation Mode. This is for selecting synchronous or asynchronous mode.

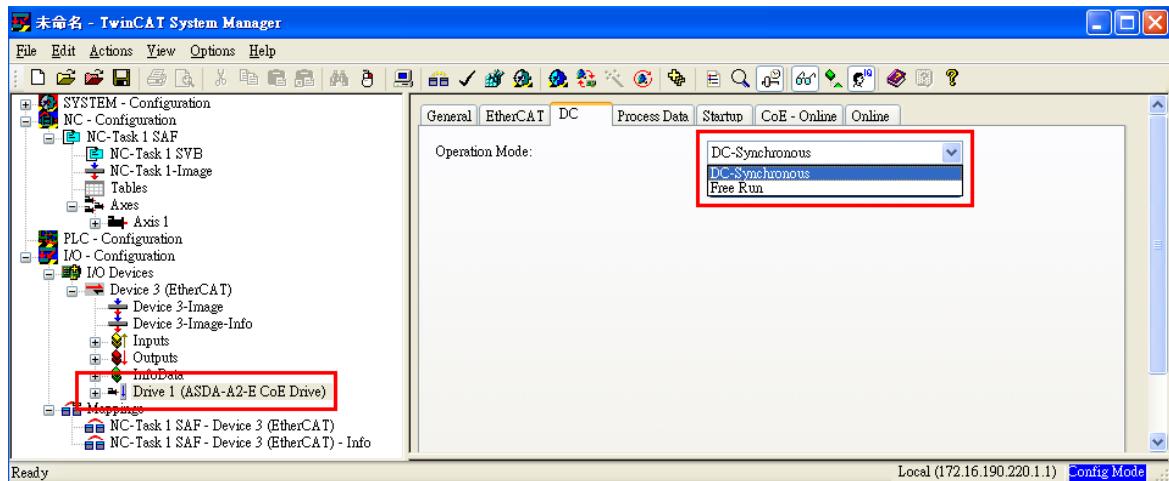


Figure 24

2.3.3 Synchronous Clock Time Setting

1. Select NC-Task 1 SAF in the left window.
2. Click Task in the right window.
3. Cycle ticks are the data exchanging period under the Task tab.

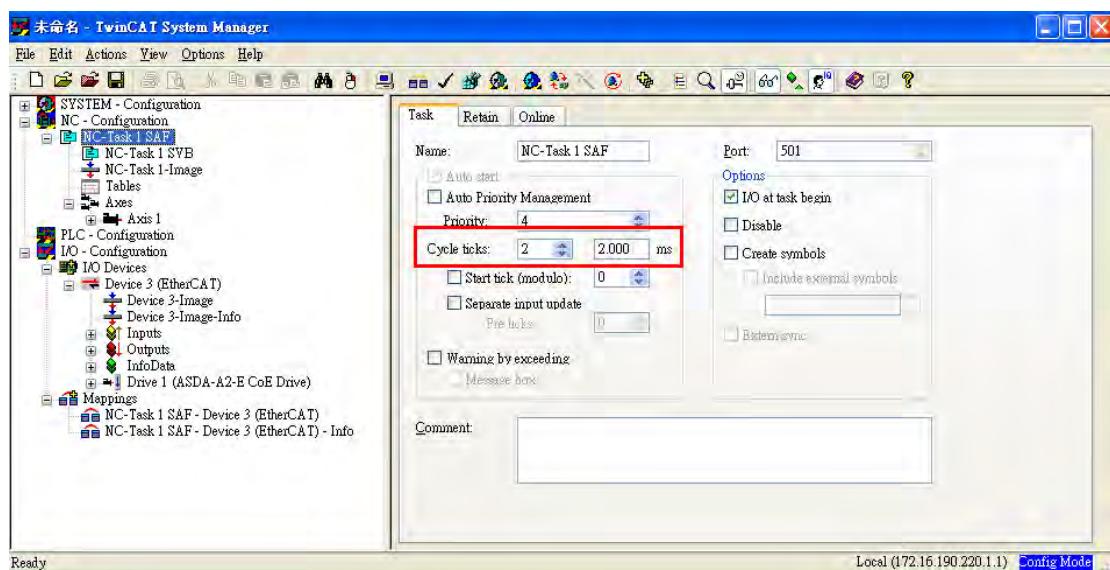


Figure 25

The unit of cycle for SYNC0 cycle time is 1ms.

SYNC0 cycle time supported	1ms (PDO cycle time = 1ms) 2ms (PDO cycle time = 2ms) 3ms (PDO cycle time = 3ms) ...
* SYNC0 cycle time is used to define PDO cycle time.	

2.4 PDO Mapping

The PDO mapping Objects are allocated from index 0x1600 to 0x1604 for RxPDOs and 0x1A00 ~ 0x1A04 for TxPDOs in Object Dictionary.

2.4.1 Default PDO Mappings

The following tables are the default PDO mappings of ASDA A2-E CoE Drive for cyclic data exchange and are also defined in EtherCAT Slave Information file (XML file).

■ 1st PDO Mapping

RxPDO (0x1600)	Control Word (0x6040)	Target Position (0x607A)	Target Velocity (0x60FF)	Target Torque (0x6071)	Mode of Operation (0x6060)
TxPDO (0x1A00)	Status Word (0x6041)	Actual Position (0x6064)	Actual Velocity (0x606C)	Actual Torque (0x6077)	Mode of Operation Display (0x6061)

■ 2nd PDO Mapping (default PDO assignment)

RxPDO (0x1601)	Control Word (0x6040)	Target Position (0x607A)
TxPDO (0x1A01)	Status Word (0x6041)	Actual Position (0x6064)

■ 3rd PDO Mapping

RxPDO (0x1602)	Control Word (0x6040)	Target Velocity (0x60FF)	
TxPDO (0x1A02)	Status Word (0x6041)	Actual Position (0x6064)	Actual Velocity (0x606C)

■ 4th PDO Mapping

RxPDO (0x1603)	Control Word (0x6040)	Target Torque (0x6071)	
TxPDO (0x1A03)	Status Word (0x6041)	Actual Position (0x6064)	Actual Torque (0x6077)

■ 5th PDO Mapping

Reserved.

2.4.2 Re-define a PDO Mapping

Setup procedure

1. Set 【RxPDO Assignment:0x1C12:0/ TxPDO Assignment: 0x1C13:0】 to 0x0 for disabling the PDO assignment.
2. Set 【RxPDO mapping entry: ex. 0x1601:0/ TxPDO mapping entry: ex. 0x1A01:0】 to 0x0 for disabling the PDO mapping entry setting.
3. Set 【RxPDO mapping entry: ex. 0x1601:0 - 0x1601:7/ TxPDO mapping entry: ex. 0x1A01:0 - 0x1A01:7】 .
4. Set 【RxPDO mapping entry: ex. 0x1601:0/ TxPDO mapping entry: ex. 0x1A01:0】 to the number of mapping entries in PDO mapping.
5. Set 【RxPDO Assignment:0x1C12:1/ TxPDO Assignment: 0x1C13:1】 to PDO assignment.
6. Set 【RxPDO Assignment:0x1C12:0/ TxPDO Assignment: 0x1C13:0】 to 0x1 for enabling the PDO assignment.

2.4.3 Using TwinCAT

1. Press **Esc** or **Shift** and **F4** to set/reset TwinCAT to Config Mode (Click OK in pop-up dialog).
2. Select Drive (ASDA A2-E CoE Drive) in the left window. In Process Data field, you can change PDO Assignment for another PDO mapping.
3. Right click the PDO Content Window, and find the PDO mapping that you desire to set, and then you can configure (Insert/Delete/Edit/Move Up/Move Down) the PDO mapping content.

(8 PDOs is the maximum number of PDO which can be assigned in every PDO mappings.)

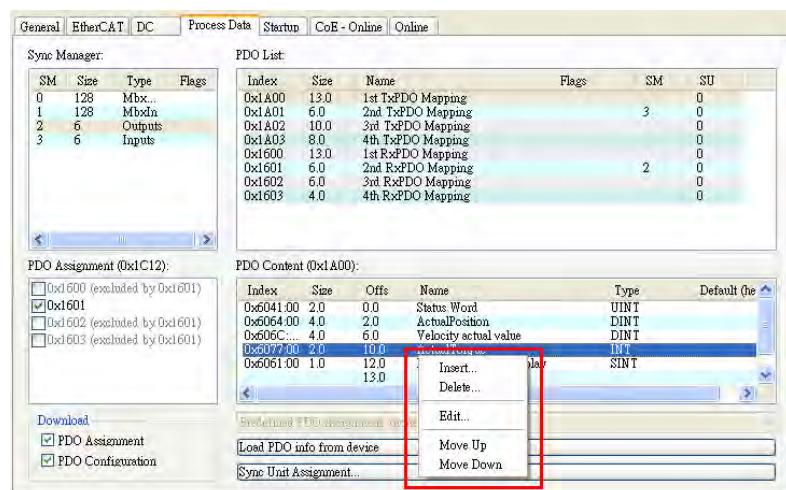


Figure 27

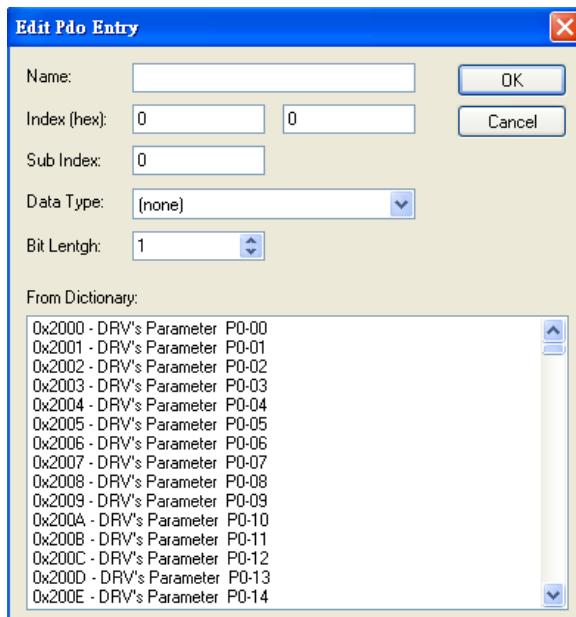


Figure 28. ASD-A2-E CoE drive Object List

4. After changing the PDO Assignment, press  or **F4** to reload I/O devices. (Click **No** in pop-up dialog and stay in Config Mode.)

Chapter 3 EtherCAT

Communication States

ASDA A2-E supports four EtherCAT communication states which are shown as below:

- Init (Initialization)
- Pre-Operational
- Safe-Operational
- Operational

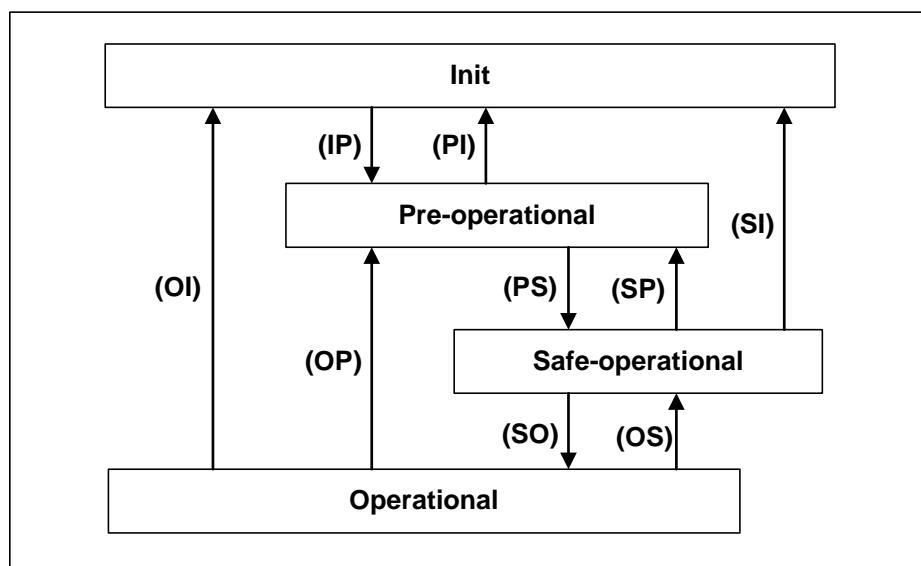


Figure 29. The EtherCAT State machine

EtherCAT host controller can switch the states. Different state provides different service.

State	Description
Init	After power on, the system will be located in this state when hardware is initialized without any error. No communication packet is sent at this stage.
Pre-Operational	The mailbox can be accessed via SDO (Service Data Object). The Emergency message will be sent to the host controller if any alarm occurs.

Safe-Operational	Except SDO, for accessing Mailbox, the PDO (Process Data Object) can only be applied for Process Data Input (TxPDO) at this stage.
Operational	The full function of SDO and PDO (TxPDO and RxPDO) are available now.

3.1 State Transition Operation

The EtherCAT host will send different state transition command for requesting different service.

State Change	Description
IP	<ul style="list-style-type: none"> Master will define the slave address and register SyncManager (0/1), and it is possible to access mailbox. Master will command the slave to switch to Safe-Operational state.
PS	<ul style="list-style-type: none"> SDO from the master will be employed for the settings of PDO mapping. Master will define FMMU and register SyncManager (2/3), and slaves keep sending the PDO (TxPDO) packets to the master. Master requests the Slave to switch to Operational state.
SO	<ul style="list-style-type: none"> Master starts to send PDO (RxPDO). The distributed clock synchronization procedure takes place between the master and slaves.
PI, SI, OI	<ul style="list-style-type: none"> All communication functions, including SDO and PDO cannot work. Switch to Init State.
SP, OP	<ul style="list-style-type: none"> Disable PDO function. Switch to Pre-Operational state
OS	<ul style="list-style-type: none"> Master stops sending Process Data Output (RxPDO). Switch to Safe-Operational state

Chapter 4 EtherCAT

Troubleshooting

Q: Why my TwinCAT cannot find EtherCAT Device from all installed NIC (Network Interface Card) and only shows RT-Ethernet devices?

A:

1. Please refer to TwinCAT setup procedure and make sure NIC is installed properly.
2. Check if the cable is correctly connected and L/A LED is lit.

Q: The dialog shows “Unknown device type found” while using TwinCAT Scan boxes.

A: Copy XML description of the ASDA-A2-E to TwinCAT device description folder (usually in **C:\TwinCAT\Io\EtherCAT**) and restart TwinCAT System.

Q: Why does EtherCAT state machine only show INIT in Current State and blank in DLL status when TwinCAT is in Config Mode?

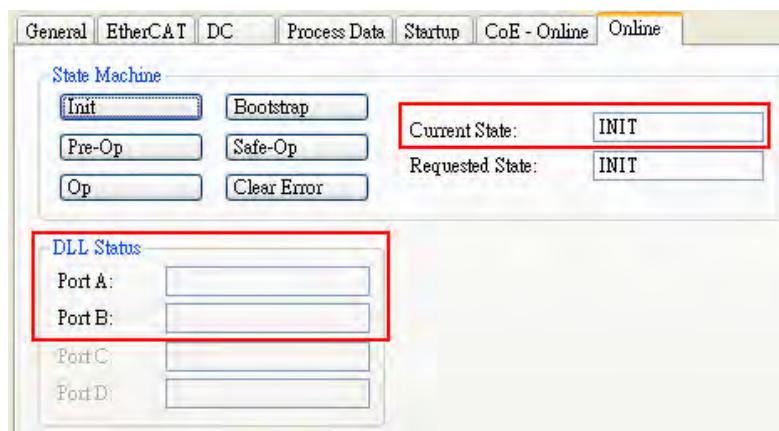


Figure 30

A:

1. Set parameter P1-01 to 0x0C (EtherCAT communication mode).
2. Check the wiring from the host to EtherCAT communication port CN6A for input and CN6B for output on servo drive. If the Link LED lit, it indicates that the physical connection is correct and the drive is connecting.

Q: TwinCAT shows “following error”.

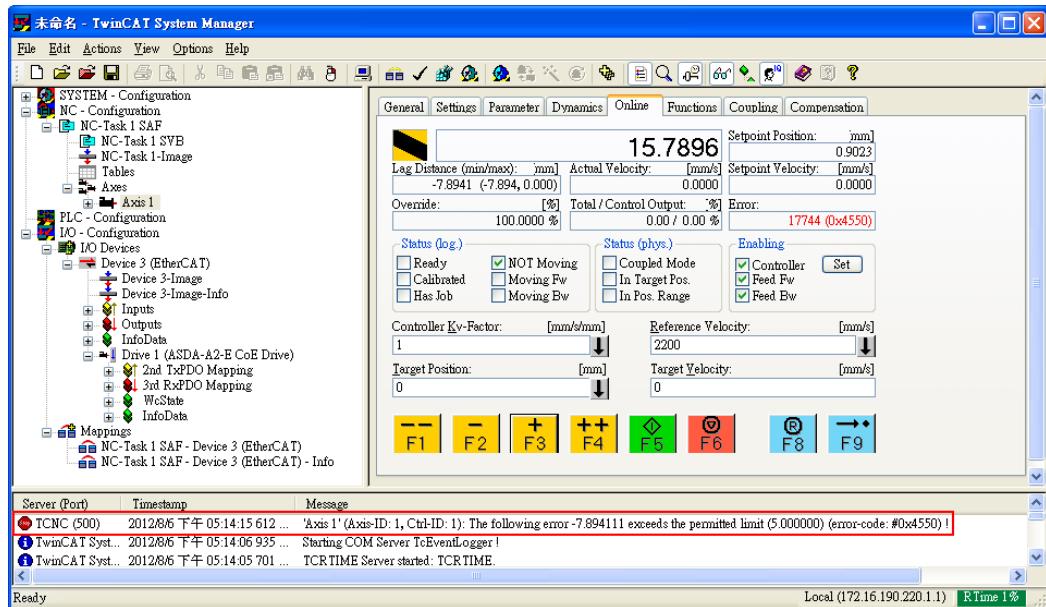


Figure 31

A: Set “Following Error Calculation” to **Extern**:

1. Select **Axis 1_Drive** in the left window.
2. In Parameter tab, select **Extern** in **Following Error Calculation**.
3. Download and click **OK** in pop-up dialog.

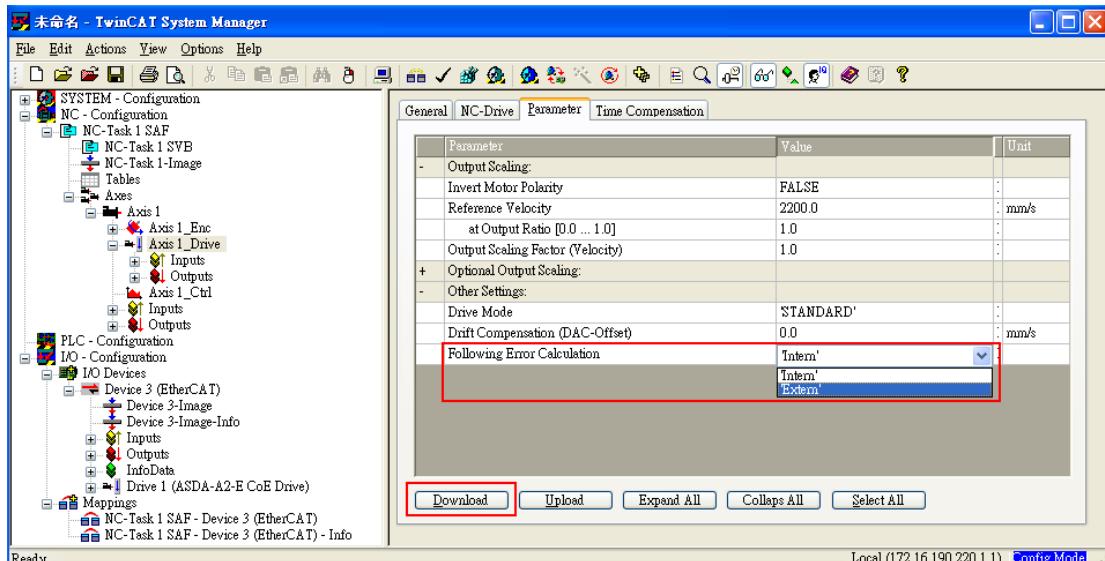


Figure 32

Q: ASDA-A2-E shows ALM.185

A: This alarm message occurs because of the disconnection of EtherCAT cable between the host and the slave. Please check the wiring. After checking the connection of the cable, it is necessary to re-servo on the drive or set OD 0x6040 to 0x86 for fault reset.

Q: ASDA-A2-E shows ALM.180

A: Working under Operational state and losing three consecutive PDOs will lead to this alarm.

1. A mechanism inside Delta Servo Drive can be used to monitor the error when receiving PDO by setting P0-02 to 121. If the number keeps increasing, it can be interpreted as the exaggerated jitter of PDO or server interference on the communication cable.
2. Select drive and click **Online**. If the number in the columns of Lost Frames and Rx Errors keeps increasing, it means the system have severe interference.

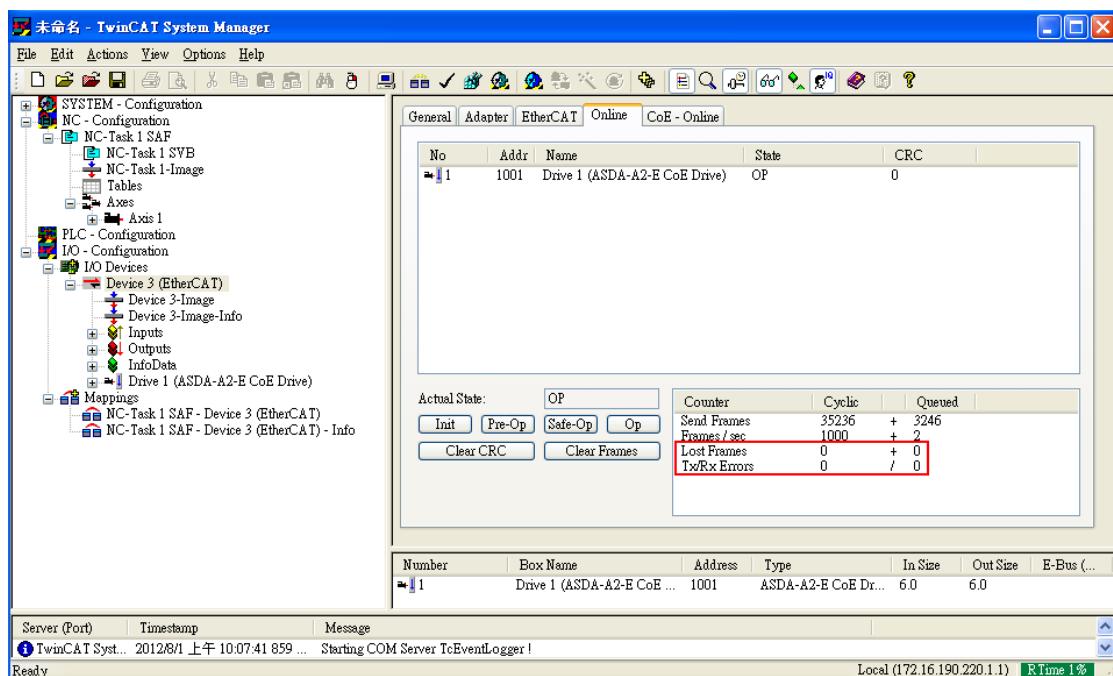


Figure 33

(This page is intentionally left blank.)

Chapter 5 CANopen Operation

Mode

5.1 Profile Position Mode

5.1.1 Description

Servo drive (hereinafter referred to as “Drive”) receives position command from the host (external) controller (hereinafter referred to as “Host”) and then controls servo motor to reach the target position.

Pulse of User-defined Unit Definition:

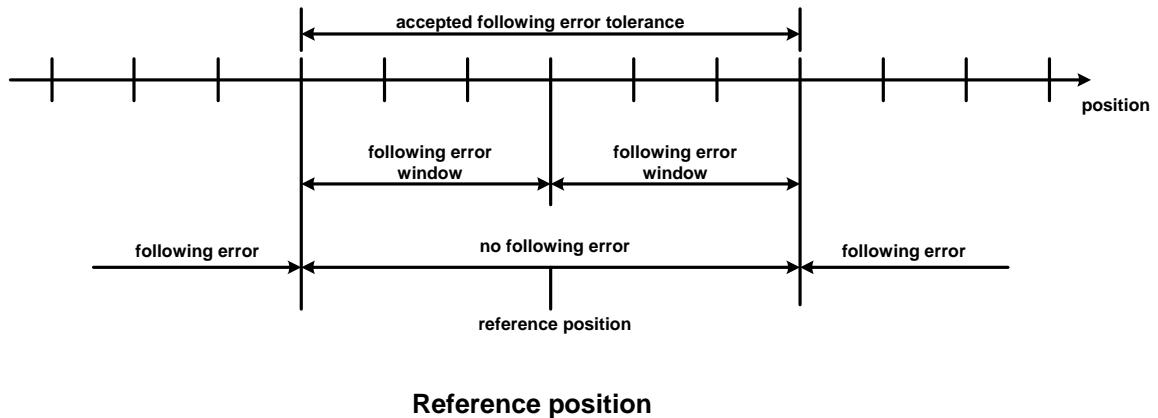
$$\text{Pulse of User Unit (PUU): No. of } \frac{\text{PUU}}{\text{Rev}} = 1280000 \times \frac{\text{OD-6393h Sub2}}{\text{OD-6093h Sub1}}$$

5.1.2 Operation Procedures

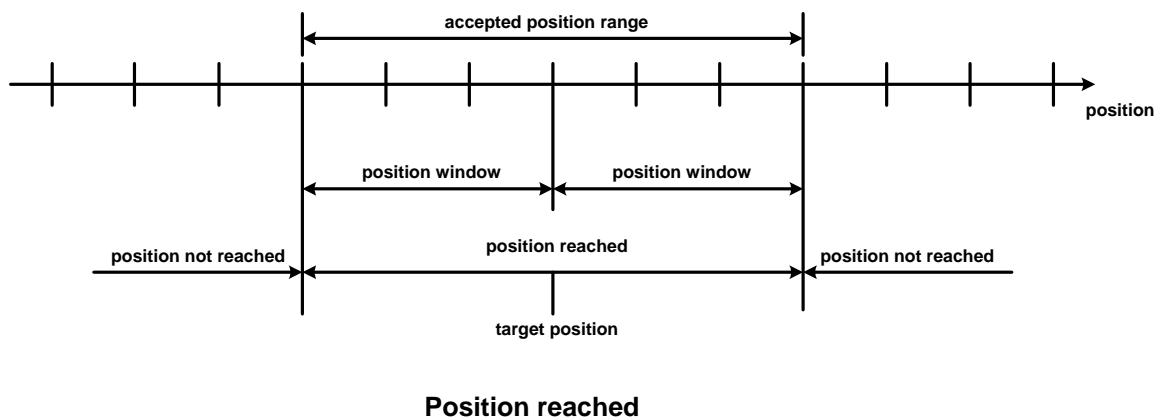
1. Set **【Mode of operations:6060h】** to profile position mode (0x01).
2. Set **【Target position:607Ah】** to the target position (unit: PUU).
3. Set **【Profile velocity:6081h】** to the profile velocity (unit: PUU per second).
4. Set **【Profile acceleration:6083h】** to plan acceleration slope (millisecond from 0rpm to 3000rpm).
5. Set **【Profile deceleration:6084h】** to plan deceleration slope (millisecond from 0rpm to 3000rpm).
6. Set **【Controlword:6040h】** as (0x06 → 0x07 → 0x0F/0x1F) to Servo On the drive and enable the motor.
7. Read **【Statusword:6064h】** to obtain feedback position of the motor.
8. Read **【Statusword:6041h】** to obtain the drive status of the following error, set-point acknowledge and target reached.

5.1.3 Advanced Setting Procedures

1. Host could obtain more information about profile position mode.
 - Read 【Position demand value:6062_h】 to obtain the internal position command. (unit: PUU)
 - Read 【Position actual value*:6063_h】 to obtain the actual position value. (unit: increments)
2. Following error
 - Set 【Following error window:6065_h】 to define the range of tolerated position value, which also defines the range of the position demand value. (unit: PUU)
 - Read 【Following error actual value:60F4_h】 to obtain the actual value of the following error. (unit: PUU)



3. Position window
 - Set 【Position window:6067_h】 to define a symmetrical range of the accepted positions which is relative to the target position. (unit: PUU)
 - Set 【Position window time:6068_h】 to plan activation time of target reached. (unit: millisecond)



5.1.4 Associated Object List

Index	Name	Type	Attr.
6040 _h	Controlword	UNSIGNED16	RW
6041 _h	Statusword	UNSIGNED16	RO
6060 _h	Modes of operation	INTEGER8	RW
6061 _h	Modes of operation display	INTEGER8	RO
6062 _h	Position demand value [PUU]	INTEGER32	RO
6063 _h	Position actual value [increment]	INTEGER32	RO
6064 _h	Position actual value	INTEGER32	RO
6065 _h	Following error window	UNSIGNED32	RW
6067 _h	Position window	UNSIGNED32	RW
6068 _h	Position window time	UNSIGNED16	RW
607A _h	Target position	INTEGER32	RW
6081 _h	Profile velocity	UNSIGNED32	RW
6083 _h	Profile acceleration	UNSIGNED32	RW
6084 _h	Profile deceleration	UNSIGNED32	RW
6093 _h	Position factor	UNSIGNED32	RW
60F4 _h	Following error actual value	INTEGER32	RO
60FC _h	Position demand value	INTEGER32	RO

5.2 Interpolation Position Mode

5.2.1 Description

The Host sends PDO periodically. With each PDO, the Host sends the next reference X_i , difference ΔX_i and controlword to the drive. While the next SYNC0 is receiving, the drive interpolates from X_{i-1} to X_i .

- Extrapolation, Jitter Compensation
 - When PDO is delayed, the interpolator will predict the speed and position for the next time according to the last acceleration.
 - When PDO delays for 2*cycle, the Drive should stop and send out an error message.
- PDO Rx/Tx Mapping record
 - The Drive receives PDOs from the Host
 - 32 bit reference position [position increment]
 - 16 bit symmetrical difference [increments]
$$\Delta X_i = (X_{i+1} - X_{i-1})/2$$
 (It is also the same as velocity.)
 - 16 bit controlword

The Drive receives PDOs from the Host (Every PDO contains 8 bytes field which is shown as below.)

32 bit reference position	16 bit difference	16 bit controlword
---------------------------	-------------------	--------------------

5.2.2 Operation Procedures

1. Set 【Mode of operations:6060_h】 to interpolation position mode(0x07).
2. Set 【Interpolation sub mode select:60C0_h】 to Interpolation mode.
 - If 60C0_h is [0], the Host does not send [60C1_h Sub-3]. It could save calculating time of the host and the Drive could also work.
 - If 60C0_h is [-1], the Host needs to send [60C1_h Sub-3] and the Drive works more precisely.
3. Set 【Interpolation time period:60C2_h】 to predict the cycle that SYNC0 receives PDO.
 - 60C2_h Sub-1 for Interpolation time units. The range is from 1ms to 20ms.
 - 60C2_h Sub-2 for Interpolation time index. The value is always -3, meaning the interpolation time unit is 10⁻³ second.
4. Drive PDO Rx:
 - 60C1_h Sub-1 for Pos Cmd (32-bit)
 - 6040_h Sub-0 for ControlWord.

5.2.3 Associated Object List

Index	Name	Type	Attr.
6040 _h	Controlword	UNSIGNED16	RW
6041 _h	Statusword	UNSIGNED16	RO
6060 _h	Modes of operation	INTEGER8	RW
6061 _h	Modes of operation display	INTEGER8	RO
6093 _h	Position factor	UNSIGNED32	RW
60C0 _h	Interpolation sub mode select	INTEGER16	RW
60C1 _h	Interpolation data record	ARRAY	RW

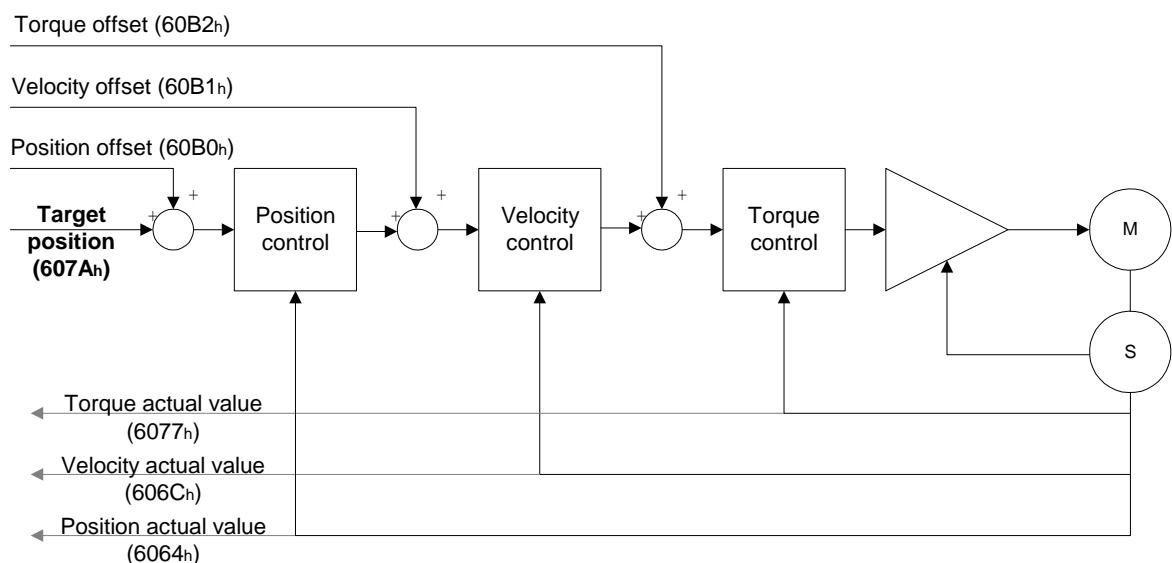
(Please refer to the following “Details of Objects” section for more detailed descriptions)

5.3 Cyclic Synchronous Position Mode

5.3.1 Description

The Host plans the path in Cyclic Synchronous Position mode and sends PDO periodically. With each PDO, the Host sends the target position and controlword to the drive. Velocity offset and torque offset can be used as velocity and torque feedforward.

5.3.2 The Function of CSP Mode



5.3.3 Operation Procedures

1. Set 【Mode of operations:6060_h】 to cyclic synchronous position mode(0x08).
2. Set 【Interpolation time period:60C2_h】 to predict the cycle that SYNC0 receives PDO.
 - 60C2_h Sub-1 for Interpolation time units. The min is from 1ms to 20ms.
 - 60C2_h Sub-2 for Interpolation time index. The value is always -3, meaning

the interpolation time unit is 10^{-3} second.

3. Drive PDO Rx:

- 607A_h for Target Pos Cmd (32-bit).
- 6040_h Sub-0 for ControlWord.

5.3.4 Associated Object List

Index	Name	Type	Attr.
6040 _h	Controlword	UNSIGNED16	RW
6041 _h	Statusword	UNSIGNED16	RO
6060 _h	Modes of operation	INTEGER8	RW
6061 _h	Modes of operation display	INTEGER8	RO
607A _h	Target position	INTEGER32	RW
60B0 _h	Position offset	INTEGER32	RW
6064 _h	Position actual value	INTEGER32	RO
60B1 _h	Velocity offset	INTEGER32	RW
606C _h	Velocity actual value	INTEGER32	RO
60B2 _h	Torque offset	INTEGER16	RW
6077 _h	Torque actual value	INTEGER16	RO

(Please refer to the following “Details of Objects” section for more detailed descriptions)

5.4 Homing Mode

5.4.1 Description

This mode could help the drive to fine the home position. Users can specify the speed, acceleration and method of homing.

5.4.2 Operation Procedures

1. Set 【Mode of operations:6060h】 to the homing mode(0x06).
2. Set 【Home offset:607Ch】.
3. Set 【Homing method:6098h】. The method range is 1 to 35. (Refer to OD-6098h definition which shows below.)
4. Set 【Homing speeds:6099h Sub-1】 in order to set speed search for switching. (unit: rpm)
5. Set 【Homing speeds:6099h Sub-2】 in order to set speed during the search for zero. (unit: rpm)
6. Set 【Homing acceleration:609Ah】 for homing acceleration. (unit: millisecond from 0rpm to 3000rpm)
7. Set 【Controlword:6040h】 to (0x06 → 0x07 → 0x0F → 0x1F) to Servo ON the drive and enable the motor.
8. Find Home Switch and do homing.
9. Read 【Statusword:6041h】 to obtain the drive status.

5.4.3 Associated Object List

Index	Name	Type	Attr.
6040h	Controlword	UNSIGNED16	RW
6041h	Statusword	UNSIGNED16	RO
6060h	Modes of operation	INTEGER8	RW
6061h	Modes of operation display	INTEGER8	RO
607Ch	Home offset	INTEGER32	RW
6093h	Position factor	UNSIGNED32	RW
6098h	Homing method	INTEGER8	RW
6099h	Homing speed	ARRAY	RW
609Ah	Homing acceleration	UNSIGNED32	RW

(Please refer to the following “Details of Objects” section for more detailed descriptions.)

5.5 Profile Velocity Mode

5.5.1 Description

The drive could receive velocity command and plan acceleration and deceleration.

5.5.2 Operation Procedures

1. Set 【Mode of operations:6060h】 to profile velocity mode(0x03).
2. Set 【Controlword:6040h】 as (0x06 → 0x07 → 0x0F/0x1F) to Servo ON the drive and enable the motor.

(After Servo On, the internal velocity command will be reset and OD-60FFh will be cleared.)

3. Set 【Profile acceleration:6083h】 to plan acceleration slope. (millisecond from 0rpm to 3000rpm)
4. Set 【Profile deceleration:6084h】 to plan deceleration slope. (millisecond from 0rpm to 3000rpm)
5. Set 【Target velocity:60FFh】 . The unit of the target velocity is 0.1rpm.

(If the drive is already servo-on, it will work immediately while receiving velocity command. OD-60FFh will be cleared to 0 if OD-6060h [Mode] is changed, and Servo-Off or Quick-Stop is activated.)

6. Read 【Statusword:6041h】 to obtain the drive status.

5.5.3 Advanced Setting Procedures

1. Host could obtain the information of velocity mode.
 - Read 【Velocity demand value:606B_h】 to inquire the internal velocity command. (unit: 0.1rpm)
 - Read 【Velocity actual value:606C_h】 to obtain the actual velocity value. (unit: 0.1rpm)
2. Host could set velocity monitor threshold.
 - Set 【Velocity window:606D_h】 to allocate velocity reached zone. (unit: 0.1rpm)
 - Set 【Velocity window time:606E_h】 in order to ensure the activation time is before velocity reached. (unit: millisecond)
 - Set 【Velocity threshold:606F_h】 to allocate zero speed level. (unit: 0.1rpm)

5.5.4 Associated Object List

Index	Name	Type	Attr.
6040 _h	Controlword	UNSIGNED16	RW
6041 _h	Statusword	UNSIGNED16	RO
6060 _h	Modes of operation	INTEGER8	RW
6061 _h	Modes of operation display	INTEGER8	RO
606B _h	Velocity demand value	INTEGER32	RO
606C _h	Velocity actual value	INTEGER32	RO

Index	Name	Type	Attr.
606D _h	Velocity window	UNSIGNED16	RW
606E _h	Velocity window time	UNSIGNED16	RW
606F _h	Velocity threshold	UNSIGNED16	RW
60FF _h	Target velocity	INTEGER32	RW

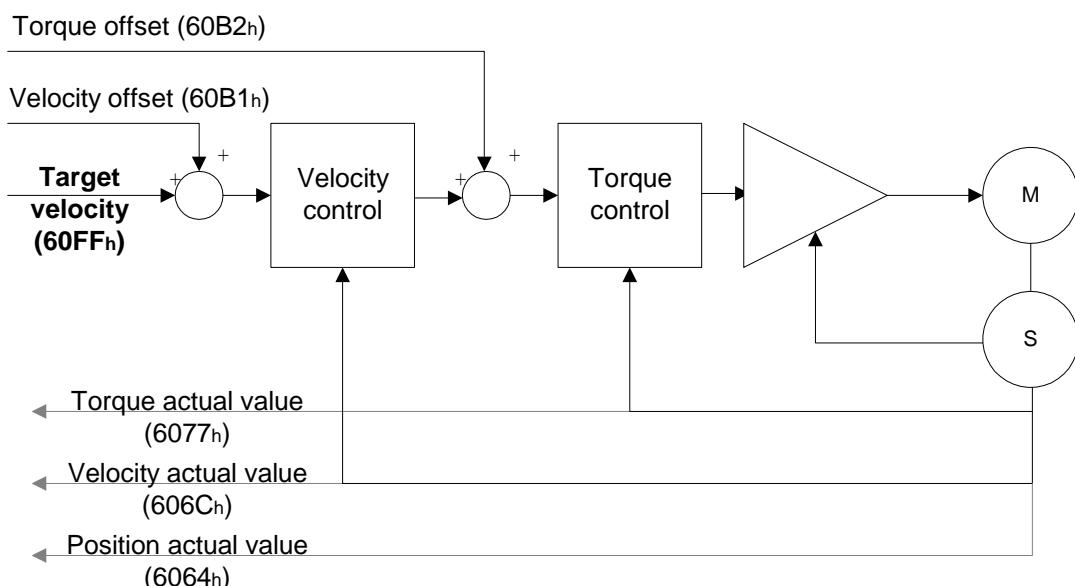
(Please refer to the following “Details of Objects” section for more detailed descriptions)

5.6 Cyclic Synchronous Velocity Mode

5.6.1 Description

The Host plans the path in Cyclic Synchronous Velocity mode. In this mode, the Host sends PDO periodically including target position and controlword to drive. In addition, velocity offset and torque offset can be used as the velocity and torque feedforward.

5.6.2 The Function of CSV Mode



5.6.3 Operation Procedures

1. Set 【Mode of operations:6060_h】 to cyclic synchronous velocity mode(0x09).
2. Set 【Interpolation time period:60C2_h】 to predict the cycle that SYNC0 receives PDO.
 - 60C2_h Sub-1 for Interpolation time units. The min is from 1ms to 20ms.
 - 60C2_h Sub-2 for Interpolation time index. The value is always -3, meaning the interpolation time unit is 10⁻³ second.

3. Drive PDO Rx:

- 60F F_h for Target Velocity Cmd (32-bit)
- 6040_h Sub-0 for ControlWord

5.6.4 Associated Object List

Index	Name	Type	Attr.
6040 _h	Controlword	UNSIGNED16	RW
6041 _h	Statusword	UNSIGNED16	RO
6060 _h	Modes of operation	INTEGER8	RW
6061 _h	Modes of operation display	INTEGER8	RO
60FF _h	Target velocity	INTEGER32	RW
60B1 _h	Velocity offset	INTEGER32	RW
606C _h	Velocity actual value	INTEGER32	RO
6064 _h	Position actual value	INTEGER32	RO
60B2 _h	Torque offset	INTEGER16	RW
6077 _h	Torque actual value	INTEGER16	RO

5.7 Profile Torque Mode

5.7.1 Description

The drive could receive torque command and plan profile torque slope.

5.7.2 Operation Procedures

1. Set 【Mode of operations:6060h】 to profile torque mode(4).
2. Set 【Controlword:6040h】 as (0x6 → 0x7 → 0x0F/0x1F) to Servo ON the drive and enable the motor.
(After Servo On the drive, the internal torque command will be reset and OD-6071h will be cleared. It means the drive is servo-on and starts to receive the torque command.)
3. Set 【Torque slope:6087h】 to plan torque slope time. (unit: millisecond from 0 to 100% rated torque)
4. Set 【Target torque:6071h】 to the target torque. The unit is given one rated torque in a thousand. (OD-6071h will be cleared to 0 if OD-6060h [Mode] changed. Servo-Off or Quick-Stop is activated.)

5.7.3 Advanced Setting Procedures

Host could obtain the information of torque mode.

- Read 【Torque demand value:6074_h】 to obtain the output value of the torque limit function. (unit: one rated torque in a thousand)
- Read 【Torque rated current:6075_h】 to obtain the rated current determined by the motor and drive type. (unit: multiples of milliamp)
- Read 【Torque actual value:6077_h】 to obtain the instantaneous torque in servo motor. (unit: one rated torque in a thousand)

- Read 【Current actual value:6078_h】 to obtain the instantaneous current in servo motor. (unit: one rated torque in a thousand)

5.7.4 Associated Object List

Index	Name	Type	Attr.
6040 _h	Controlword	UNSIGNED16	RW
6041 _h	Statusword	UNSIGNED16	RO
6060 _h	Modes of operation	INTEGER8	RW
6061 _h	Modes of operation display	INTEGER8	RO
6071 _h	Target torque	INTEGER16	RW
6074 _h	Torque demand value	INTEGER16	RO
6075 _h	Motor rated current	UNSIGNED32	RO
6077 _h	Torque actual value	INTEGER16	RO
6078 _h	Current actual value	INTEGER16	RO
6087 _h	Torque slope	UNSIGNED32	RW

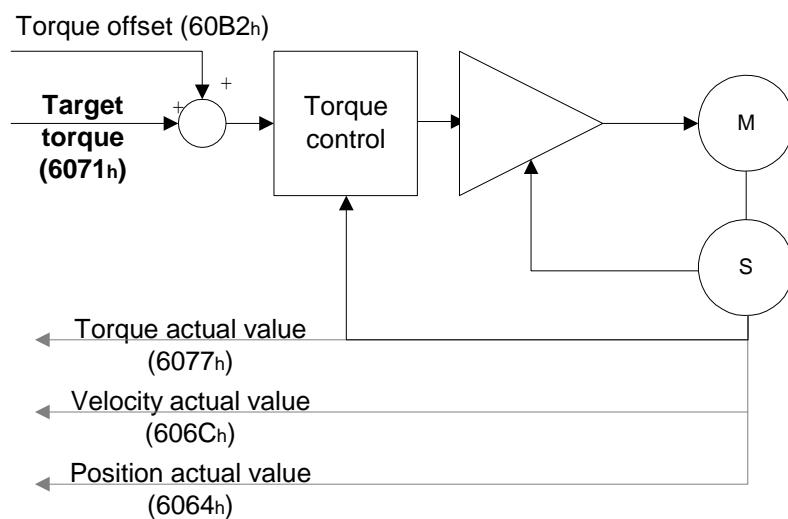
(Please refer to the following “Details of Objects” section for more detailed descriptions.)

5.8 Cyclic Synchronous Torque Mode

5.8.1 Description

The Host plans the path in Cyclic Synchronous Torque mode. In this mode, the Host sends PDO periodically including target position and controlword to drive. In addition, velocity offset and torque offset can be used as the velocity and torque feedforwad.

5.8.2 The Function of CST Mode



5.8.3 Operation Procedures

1. Set 【Mode of operations:6060_h】 to cyclic synchronous torque mode (0x0A).
2. Set 【Interpolation time period:60C2_h】 to predict the cycle that SYNC0 receives PDO.
 - 60C2_h Sub-1 for Interpolation time units. The min is from 1ms to 20ms.
 - 60C2_h Sub-2 for Interpolation time index. The value is always -3, meaning the interpolation time unit is 10⁻³ second.
3. Drive PDO Rx:
 - 60FF_h for Target Torque Cmd (16-bit)
 - 6040_h Sub-0 for ControlWord.

5.8.4 Associated Object List

Index	Name	Type	Attr.
6040 _h	Controlword	UNSIGNED16	RW
6041 _h	Statusword	UNSIGNED16	RO
6060 _h	Modes of operation	INTEGER8	RW
6061 _h	Modes of operation display	INTEGER8	RO
6071 _h	Target torque	INTEGER16	RW
60B2 _h	Torque offset	INTEGER16	RW
6077 _h	Torque actual value	INTEGER16	RO
606C _h	Velocity actual value	INTEGER32	RO
6064 _h	Position actual value	INTEGER32	RO

(Please refer to the following “Details of Objects” section for more detailed descriptions)

5.9 Limit Position Handling Procedure

5.9.1 Description

Drive will switch to Quick-Stop status while traveling to the position of positive or negative limit sensors, and it can be handled by the following procedures.

5.9.2 Operation Procedures

1. The servo panel will show the alarm while sensors are close to the positive or negative limit. The motor is controlled by a deceleration slope to stop and it is at Quick-Stop status. The drive will keep in servo-on status but will not accept the further motion command.
2. Set **【Controlword:6040h】** to 0x8F for fault reset and clearing the alarm displayed on the panel.
3. Set **【Controlword:6040h】** to 0x1F/0x0F for Operation Enabled, and then the servo can accept the motion command again.
4. For a motor at its limit position, there must be a command which can drive the motor to the backward direction. Or the alarm will be triggered again while the motor starts moving.

5.10 Touch Probe Function

5.10.1 Description

Touch Probe function can be enabled by the DI on CN7 or the encoder; among that, the feedback position can be latched as positive or negative edge with two dedicated DI on CN7. The time of latch position is shorter than 5 μ s and it is used to execute high speed performance in measuring or packaging applications.

5.10.2 Touch Probe Function

The current status of Touch Probe can be obtained by object 60B8h. The definition of each bit is as the followings.

Bit	Value	Definition
0	0	Switch off touch probe 1
	1	Enable touch probe 1
1	0	Trigger first event
	1	Continuous
2	0	Trigger with touch probe 1 input
	1	Trigger with zero impulse signal
3	0	Reserved
4	0	Switch off sampling at positive edge of touch probe 1
	1	Enable sampling at positive edge of touch probe 1
5	0	Switch off sampling at negative edge of touch probe 1
	1	Enable sampling at negative edge of touch probe 1
6 ~ 7	0	Reserved
8	0	Switch off touch probe 2
	1	Enable touch probe 2
9	0	Trigger first event
	1	Continuous

10	0	Trigger with touch probe 2 input
	1	Trigger with zero impulse signal
11	0	Reserved
12	0	Switch off sampling at positive edge of touch probe 2
	1	Enable sampling at positive edge of touch probe 2
13	0	Switch off sampling at negative edge of touch probe 2
	1	Enable sampling at negative edge of touch probe 2
14 ~ 15		Reserved

5.10.3 Touch Probe Status

The current status of Touch Probe can be obtained by object 60B9h. The definition of each bit is as the followings.

Bit	Value	Definition
0	0	Touch probe 1 is switched off
	1	Touch probe 1 is enabled
1	0	Touch probe 1 has no positive edge value stored
	1	Touch probe 1 has positive edge value stored
2	0	Touch probe 1 has no negative edge value stored
	1	Touch probe 1 has negative edge value stored
3 ~ 5	0	Reserved
6	0	Trigger with touch probe 1 input
	1	Trigger with zero impulse signal
7	0	Touch probe 1 input off
	1	Touch probe 1 input on

8	0	Touch probe 2 is switched off
	1	Touch probe 2 is enabled
9	0	Touch probe 2 has no positive edge value stored
	1	Touch probe 2 has positive edge value stored
10	0	Touch probe 2 has no negative edge value stored
	1	Touch probe 2 has negative edge value stored
11 ~ 13	0	Reserved
14	0	Trigger with touch probe 2 input
	1	Trigger with zero impulse signal
15	0	Touch probe 2 input off
	1	Touch probe 2 input on

5.10.4 Associated Object List

Index	Name	Type	Attr.
60B8 _h	Touch probe function	UNSIGNED16	RW
60B9 _h	Touch probe status	UNSIGNED16	RO
60BA _h	Touch probe pos1 pos value	INTEGER32	RO
60BB _h	Touch probe pos1 neg value	INTEGER32	RO
60BC _h	Touch probe pos2 pos value	INTEGER32	RO
60BD _h	Touch probe pos2 neg value	INTEGER32	RO

(Please refer to the following "Details of Objects" section for more detailed descriptions)

(This page is intentionally left blank.)

Chapter 6 Object Dictionary

Entries

6.1 Specifications for Objects

6.1.1 Object Type

Object Name	Comments
VAR	A single value such as an UNSIGNED8, Boolean, float, INTEGER16 etc.
ARRAY	A multiple data field object where each data field is a sample variable of the SAME basic data type e.g. array of UNSIGNED16 etc. Sub-index 0 is UNSIGNED8 but is not part of the ARRAY data
RECORD	A multiple data field object where the data fields may be any combination of simple variables. Sub-index 0 is UNSIGNED8 but is not part of the RECORD data

6.1.2 Data Type

Please refer to CANopen Standard 301.

6.2 Overview of Object Group 1000_h

Index	Object Type	Name	Data Type	Access
1000 _h	VAR	device type	UNSIGNED32	RO
1001 _h	VAR	error register	UNSIGNED8	RO
1600 _h ~04 _h	RECORD	Receive PDO mapping	UNSIGNED32	RW
1A00 _h ~03 _h	RECORD	Transmit PDO mapping	UNSIGNED32	RW

※ Only 1001_h could be mapped to PDO.

6.3 Overview of Object Group 6000_h

Index	Object Type	Name	Data Type	Access	Mappable
603F _h	VAR	Error Code	UNSIGNED16	RO	Y
6040 _h	VAR	Controlword	UNSIGNED16	RW	Y
6041 _h	VAR	Statusword	UNSIGNED16	RO	Y
605B _h	VAR	Shutdown option code	INTEGER16	RW	N
605E _h	VAR	Fault reaction option code	INTEGER16	RW	N
6060 _h	VAR	Modes of operation	INTEGER8	RW	Y
6061 _h	VAR	Modes of operation display	INTEGER8	RO	Y
6062 _h	VAR	Position demand value [PUU]	INTEGER32	RO	Y
6063 _h	VAR	Position actual value [increment]	INTEGER32	RO	Y
6064 _h	VAR	Position actual value	INTEGER32	RO	Y
6065 _h	VAR	Following error window	UNSIGNED32	RW	Y
6067 _h	VAR	Position windows	UNSIGNED32	RW	Y
6068 _h	VAR	Position window time	UNSIGNED16	RW	Y
606B _h	VAR	Velocity demand value	INTEGER32	RO	Y
606C _h	VAR	Velocity actual value	INTEGER32	RO	Y
606D _h	VAR	Velocity window	UNSIGNED16	RW	Y
606E _h	VAR	Velocity window time	UNSIGNED16	RW	Y
606F _h	VAR	Velocity threshold	UNSIGNED16	RW	Y
6071 _h	VAR	Target torque	INTEGER16	RW	Y
6072 _h	VAR	Max torque	UNSIGNED16	RW	Y
6074 _h	VAR	Torque demand value	INTEGER16	RO	Y
6075 _h	VAR	Motor rated current	UNSIGNED32	RO	Y
6076 _h	VAR	Motor rated torque	UNSIGNED32	RO	Y
6077 _h	VAR	Torque actual value	UNSIGNED16	RO	Y
6078 _h	VAR	Current actual value	INTEGER16	RO	Y

Index	Object Type	Name	Data Type	Access	Mappable
607A _h	VAR	Target position	INTEGER32	RW	Y
607C _h	VAR	Home Offset	INTEGER32	RW	Y
607D _h	ARRAY	Software position limit	INTEGER32	RW	Y
607E _h	VAR	Polarity	UNSIGNED8	RW	Y
607F _h	VAR	Max profile velocity	UNSIGNED32	RW	Y
6080 _h	VAR	Max motor speed	UNSIGNED32	RW	Y
6081 _h	VAR	Profile velocity	UNSIGNED32	RW	Y
6083 _h	VAR	Profile acceleration	UNSIGNED32	RW	Y
6084 _h	VAR	Profile deceleration	UNSIGNED32	RW	Y
6085 _h	VAR	Quick stop deceleration	UNSIGNED32	RW	Y
6086 _h	VAR	Motion profile type	INTEGER16	RW	Y
6087 _h	VAR	Torque slope	UNSIGNED32	RW	Y
6093 _h	ARRAY	Position factor	UNSIGNED32	RW	Y
6098 _h	VAR	Homing method	INTEGER8	RW	Y
6099 _h	ARRAY	Homing speeds	UNSIGNED32	RW	Y
609A _h	VAR	Homing acceleration	UNSIGNED32	RW	Y
60B0 _h	VAR	Position offset	INTEGER32	RW	Y
60B1 _h	VAR	Velocity offset	INTEGER32	RW	Y
60B2 _h	VAR	Torque offset	INTEGER16	RW	Y
60B8 _h	VAR	Touch probe function	UNSIGNED16	RW	Y
60B9 _h	VAR	Touch probe status	UNSIGNED16	RO	Y
60BA _h	VAR	Touch probe pos1 pos value	INTEGER32	RO	Y
60BB _h	VAR	Touch probe pos1 neg value	INTEGER32	RO	Y
60BC _h	VAR	Touch probe pos2 pos value	INTEGER32	RO	Y
60BD _h	VAR	Touch probe pos2 neg value	INTEGER32	RO	Y
60C0 _h	VAR	Interpolation sub mode	INTEGER16	RW	Y

Index	Object Type	Name	Data Type	Access	Mappable
		select			
60C1 _h	ARRAY	Interpolation data record	UNSIGNED16/32	RW	Y
60C2 _h	RECORD	Interpolation time period	SIGNED8	RW	Y
60C5 _h	VAR	Max acceleration	UNSIGNED32	RW	Y
60C6 _h	VAR	Max deceleration	UNSIGNED32	RW	Y
60F2 _h	VAR	Positioning option code	UNSIGNED16	RW	Y
60F4 _h	VAR	Following error actual value	INTEGER32	RO	Y
60FC _h	VAR	Position demand value	INTEGER32	RO	Y
60FD _h	VAR	Digital inputs	UNSIGNED32	RO	Y
60FF _h	VAR	Target velocity	INTEGER32	RW	Y
6502 _h	VAR	Supported drive modes	UNSIGNED32	RO	Y
Delta parameter definition					
2xxx	VAR	Parameter Mapping	INTEGER16/32	RW	Y

6.4 Details of Objects

Object 1000_h: Device Type

INDEX	1000 _h
Name	device type
Object Code	VAR
Data Type	UNSIGNED32
Access	RO
PDO Mapping	No
Value Range	UNSIGNED32
Default Value	04020192 _h : A2 Series 06020192 _h : M Series

Object 1001_h: Error Register

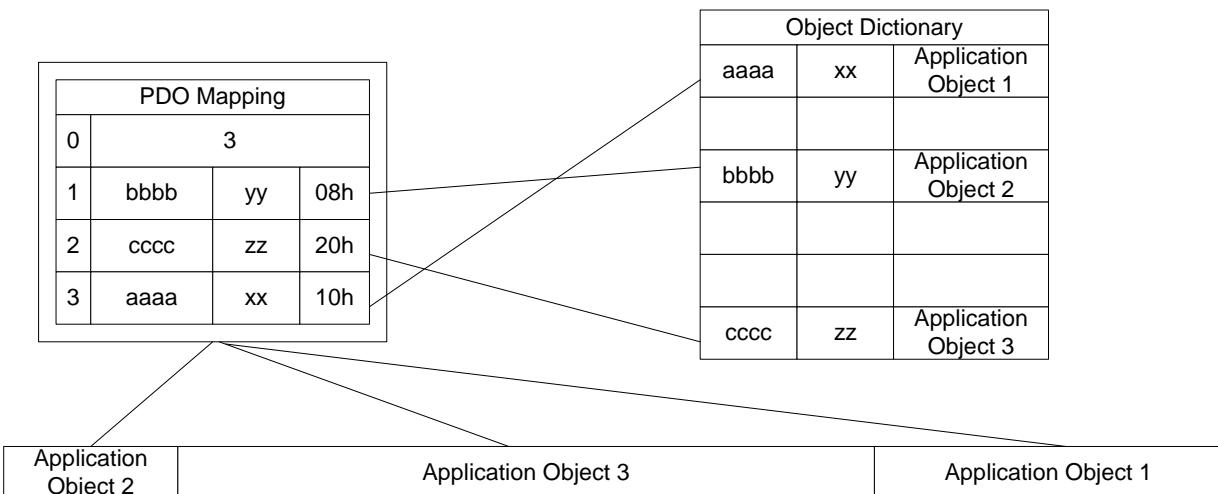
INDEX	1001 _h
Name	error register
Object Code	VAR
Data Type	UNSIGNED8
Access	RO
PDO Mapping	Yes
Value Range	UNSIGNED8
Default Value	0

Object 1600_h ~ 1604_h: Receive PDO Mapping Parameter

INDEX	1600 _h ~ 1604 _h
Name	Receive PDO mapping
Object Code	RECORD
Data Type	PDO Mapping
Access	RW
PDO Mapping	No

Sub-Index	0
Description	Number of mapped application objects in PDO
Data Type	UNSIGNED8
Access	RW
PDO Mapping	No
Value Range	0: deactivated 1~8: activated
Default Value	0

Sub-Index	1~8
Description	PDO mapping for the nth application object to be mapped
Data Type	UNSIGNED32
Access	RW
PDO Mapping	No
Value Range	UNSIGNED32
Default Value	0



Object 1A00_h ~ 1A04_h: Transmit PDO Mapping Parameter

INDEX	1A00 _h ~ 1A04 _h
Name	Transmit PDO mapping
Object Code	RECORD
Data Type	PDO Mapping
Access	RW
PDO Mapping	No

Sub-Index	0
Description	Number of mapped application objects in PDO
Data Type	UNSIGNED8
Access	RW
PDO Mapping	No
Value Range	0: deactivated 1~8: activated
Default Value	0

Sub-Index	1~8
Description	PDO mapping for the nth application object to be mapped
Data Type	UNSIGNED32
Access	RW
PDO Mapping	No
Value Range	UNSIGNED32
Default Value	0

Object 1C12_h : RxPDO assign

INDEX	1C12 _h
Name	RxPDO assign
Object Code	RECORD
Data Type	PDO Mapping assign
Access	RW
PDO Mapping	No

Sub-Index	0
Description	Number of assigned PDO mapping
Data Type	UNSIGNED8
Access	RW
PDO Mapping	No
Value Range	0: deactivated 1: One PDO mapping be assigned to SycManager2 for RxPDO
Default Value	1

Sub-Index	1
Description	Index of assigned PDO mapping
Data Type	UNSIGNED16
Access	RW
PDO Mapping	No
Value Range	1600 _h to 1604 _h
Default Value	1601 _h

Object 1C13_h : TxPDO assign

INDEX	1C13 _h
Name	TxPDO assign
Object Code	RECORD
Data Type	PDO Mapping assign
Access	RW
PDO Mapping	No

Sub-Index	0
Description	Number of assigned PDO mapping
Data Type	UNSIGNED8
Access	RW
PDO Mapping	No
Value Range	0: deactivated 1: One PDO mapping be assigned to SycManager3 for TxPDO
Default Value	1

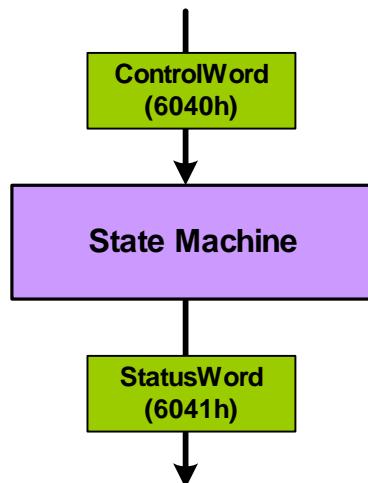
Sub-Index	1
Description	Index of assigned PDO mapping
Data Type	UNSIGNED16
Access	RW
PDO Mapping	No
Value Range	1A00 _h to 1A04 _h
Default Value	1A01 _h

Object 603F_h: Error code (error code of CANopen defined)

INDEX	603F _h
Name	Errorcode
Object Code	VAR
Data Type	UNSIGNED16
Access	RO
PDO Mapping	Yes
Value Range	UNSIGNED16
Default Value	0

Object 6040_h: Controlword

INDEX	6040 _h
Name	Controlword
Object Code	VAR
Data Type	UNSIGNED16
Access	RW
PDO Mapping	Yes
Value Range	UNSIGNED16
Default Value	P1-01 = 0x0C, Default is 0x0004



State machine in system context

Bit Definition

15~9	8	7	6~4	3	2	1	0
N/A	Halt	Fault reset	Operation mode specific	Enable operation	Quick Stop (B-contact)	Enable voltage	Switch on

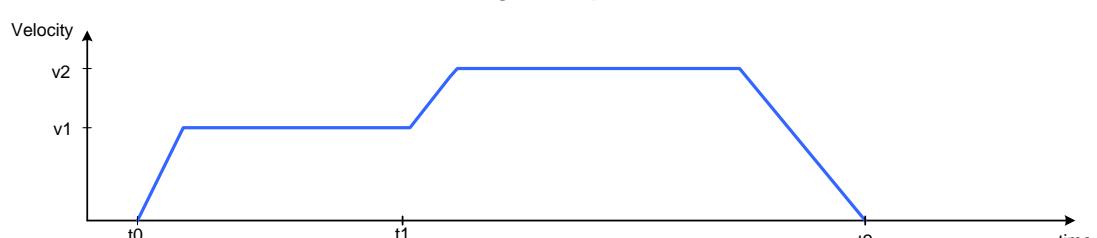
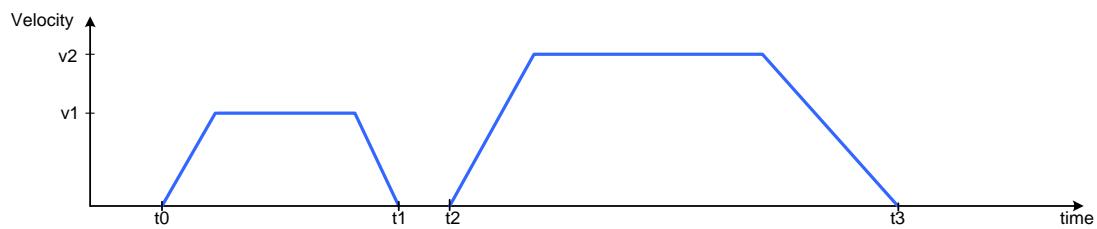
Note :

The user needs to set 6040h to 0x0006->0x0007->0x000F for Servo On step by step.

Bit	Operation mode				
	PP	HM	IP	PV	PT
4	New set-point (positive trigger)	Homing operation start (positive trigger)	N/A	N/A	N/A
5	Change set immediately	N/A	N/A	N/A	N/A
6	Absolute(0) / relative(1)	N/A	N/A	N/A	N/A

Abbreviation:

- PP** Profile Position Mode
- HM** Homing Mode
- IP** Interpolated Position Mode
- PV** Profile Velocity Mode
- PT** Profile Torque Mode



Object 6041_h: Statusword

INDEX	6041 _h
Name	Statusword
Object Code	VAR
Data Type	UNSIGNED16
Access	RO
PDO Mapping	Yes
Value Range	UNSIGNED16
Default Value	0

Data Description

15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0
----	----	----	----	----	----	---	---	---	---	---	---	---	---	---	---

MSB

LSB

Bit Definition

0	Ready to switch on
1	Switch on
2	Operation enabled (status of servo on)
3	Fault (the drive will servo off)
4	Voltage enabled
5	Quick stop
6	Switch on disabled
7	Warning (the drive is still servo on)

8	N/A				
9	Remote				
10	Target reached				
11	Internal limit active (Not supported)				
	PP	HM	IP	PV	PT
12	Set-point acknowledge	Homing attained	IP mode active	Zero Speed	N/A
13	Following error	Homing error	N/A	N/A	N/A
14	N/A	N/A	N/A	N/A	N/A
15	N/A	N/A	N/A	N/A	N/A

Note:

Set-point acknowledge: Trajectory generator has assumed the positioning values

Homing attained: Homing mode carried out successfully

IP mode active: interpolated position mode active – mode is running in IP mode

SYNC OK: SYNC frame is reached before the path generator starts

Object 605B_h: Shutdown option code

INDEX	605B _h
Name	Shutdown option code
Object Code	VAR
Data Type	INTEGER16
Access	RW
PDO Mapping	Yes
Value Range	INTEGER16
Default Value	0
Comment	0:Disable drive function -1:Dynamic break enable

Object 605E_h: Fault reaction option code

INDEX	605E _h
Name	Fault reaction option code
Object Code	VAR
Data Type	INTEGER16
Access	RW
PDO Mapping	Yes
Value Range	INTEGER16
Default Value	2
Comment	0:Disable drive, motor is free to rotate 1:slow down on slow down ramp 2:slow down on quick stop ramp

Object 6060_h: Modes of operation

INDEX	6060 _h
Name	Modes of operation
Object Code	VAR
Data Type	INTEGER8
Access	RW
PDO Mapping	Yes
Value Range	INTEGER8
Default Value	0
Comment	0: Reserved 1: Profile position mode 3: Profile velocity mode 4: Profile torque mode 6: Homing mode 7: Interpolated position mode 8: Cyclic synchronous position mode 9: Cyclic synchronous velocity mode 10: Cyclic synchronous torque mode

Object 6061_h: Modes of operation display

INDEX	6061 _h
Name	Modes of operation display
Object Code	VAR
Data Type	INTEGER8
Access	RW
PDO Mapping	Yes
Value Range	INTEGER8
Default Value	0

Object 6062_h: Position demand value

INDEX	6062 _h
Name	Position demand value
Object Code	VAR
Data Type	INTEGER32
Access	RO
PDO Mapping	Yes
Value Range	INTEGER32
Default Value	0
Comment	Position command is calculated by Interpolation theory Unit: PUU

Object 6063_h: Position demand value

INDEX	6063 _h
Name	Position actual value*
Object Code	VAR
Data Type	INTEGER32
Access	RO
PDO Mapping	Yes
Value Range	INTEGER32
Default Value	0
Comment	Unit: increments

Object 6064_h: Position actual value

INDEX	6064 _h
Name	Position actual value
Object Code	VAR
Data Type	INTEGER32
Access	RO
PDO Mapping	Yes
Value Range	INTEGER32
Default Value	0
Comment	Unit: PUU

Object 6065_h: Following error window

INDEX	6065 _h
Name	Following error window
Object Code	VAR
Data Type	UNSIGNED32
Access	RW
PDO Mapping	Yes
Value Range	UNSIGNED32
Default Value	3840000
Comment	Unit: PUU

Object 6067_h: Position window

INDEX	6067 _h
Name	Position window
Object Code	VAR
Data Type	UNSIGNED32
Access	RW
PDO Mapping	Yes
Value Range	UNSIGNED32
Default Value	100
Comment	Unit: PUU

Object 6068_h: Position window time

INDEX	6068 _h
Name	Position window time
Object Code	VAR
Data Type	UNSIGNED16
Access	RW
PDO Mapping	Yes
Value Range	UNSIGNED16
Default Value	0
Comment	Unit: millisecond

Object 606B_h: Velocity demand value

INDEX	606B _h
Name	Velocity demand value
Object Code	VAR
Data Type	INTEGER32
Access	RO
PDO Mapping	Yes
Value Range	INTEGER32
Comment	Unit: 0.1rpm

Object 606C_h: Velocity actual value

INDEX	606C _h
Name	Velocity actual value
Object Code	VAR
Data Type	INTEGER32
Access	RO
PDO Mapping	Yes
Value Range	INTEGER32
Comment	Unit: 0.1rpm

Object 606D_h: Velocity window

INDEX	606D _h
Name	Velocity window
Object Code	VAR
Data Type	INTEGER16
Access	RO
PDO Mapping	Yes
Value Range	0~3000
Default Value	100
Comment	Unit: 0.1rpm

Object 606E_h: Velocity window time

INDEX	606E _h
Name	Velocity window time
Object Code	VAR
Data Type	UNSIGNED16
Access	RW
PDO Mapping	Yes
Value Range	UNSIGNED16
Default Value	0
Comment	Unit: millisecond

Object 606F_h: Velocity threshold

INDEX	606F _h
Name	Velocity threshold
Object Code	VAR
Data Type	UNSIGNED16
Access	RW
PDO Mapping	Yes
Value Range	0~2000
Default Value	100
Comment	Unit: 0.1rpm

Object 6071_h: Target torque

INDEX	6071 _h
Name	Target torque
Object Code	VAR
Data Type	INTEGER16
Access	RW
PDO Mapping	Yes
Value Range	-3000~3000
Default Value	0
Comment	Unit: one rated torque in a thousand

Object 6072_h: Max torque

INDEX	6072 _h
Name	Max torque
Object Code	VAR
Data Type	UNSIGNED16
Access	RW
PDO Mapping	Yes
Value Range	0~3000
Default Value	3000
Comment	Unit: one rated torque in a thousand

Object 6074_h: Torque demand value

INDEX	6074 _h
Name	Torque demand value
Object Code	VAR
Data Type	INTEGER16
Access	RO
PDO Mapping	Yes
Value Range	INTEGER16
Comment	Unit: one rated torque in a thousand

Object 6075_h: Motor rated current

INDEX	6075 _h
Name	Motor rated current
Object Code	VAR
Data Type	UNSIGNED32
Access	RO
PDO Mapping	Yes
Value Range	UNSIGNED32
Comment	Unit: milliamp

Object 6076_h: Motor rated torque

INDEX	6076 _h
Name	Motor rated torque
Object Code	VAR
Data Type	UNSIGNED32
Access	RO
PDO Mapping	Yes
Value Range	UNSIGNED32
Comment	Unit: one rated torque in a thousand

Object 6077_h: Torque actual value

INDEX	6077 _h
Name	Torque actual value
Object Code	VAR
Data Type	INTEGER16
Access	RO
PDO Mapping	Yes
Value Range	INTEGER16
Comment	Unit: one rated torque in a thousand

Object 6078_h: Current actual value

INDEX	6078 _h
Name	Current actual value
Object Code	VAR
Data Type	INTEGER16
Access	RO
PDO Mapping	Yes
Value Range	INTEGER16
Comment	Unit: one rated current in a thousand

Object 607A_h: Target position

INDEX	607A _h
Name	Target position
Object Code	VAR
Data Type	INTEGER32
Access	RW
PDO Mapping	Yes
Value Range	INTEGER32
Default Value	0
Comment	For Profile position mode 6060 _h =1 Unit: PUU

Object 607C_h: Home offset

INDEX	607C _h
Name	Home offset
Object Code	VAR
Data Type	INTEGER32
Access	RW
PDO Mapping	Yes
Value Range	INTEGER32
Default Value	0
Comment	Unit : PUU



Object 607D_h: Software position limit

INDEX	607D _h
Name	Software position limit
Object Code	ARRAY
Data Type	INTEGER32
Access	RW
PDO Mapping	Yes

Sub-Index	0
Description	Number of entries
Data Type	UNSIGNED8
Access	RO
PDO Mapping	Yes
Value Range	2
Default Value	2
Sub-Index	1
Description	Min position limit
Data Type	INTEGER32
Access	RW
PDO Mapping	Yes
Value Range	-2147483648 ~ +2147483647
Default Value	-2147483648
Comment	Unit: PUU

Sub-Index	2
Description	Max position limit
Data Type	INTEGER32
Access	RW
PDO Mapping	Yes
Value Range	-2147483648 ~ +2147483647

Default Value	+2147483647
Comment	Unit: PUU

Object 607F_h: Max profile velocity

INDEX	607F _h
Name	Max profile velocity
Object Code	VAR
Data Type	UNSIGNED32
Access	RW
PDO Mapping	Yes
Value Range	UNSIGNED32
Default Value	P1-55(rpm) * 10
Comment	Unit:0.1rpm

Object 6080_h: Max motor speed

INDEX	6080 _h
Name	Max motor speed
Object Code	VAR
Data Type	UNSIGNED32
Access	RW
PDO Mapping	Yes
Value Range	UNSIGNED32
Default Value	P1-55(rpm)
Comment	Unit: rpm

Object 6081_h: Profile velocity

INDEX	6081 _h
Name	Profile Velocity
Object Code	VAR
Data Type	UNSIGNED32
Access	RW
PDO Mapping	Yes
Value Range	UNSIGNED32
Default Value	10000

Comment	For Profile position mode 6060h=1 Unit: PUU per second
---------	---

Object 6083h: Profile acceleration

INDEX	6083h
Name	Profile acceleration
Object Code	VAR
Data Type	UNSIGNED32
Access	RW
PDO Mapping	Yes
Value Range	1~UNSIGNED32
Default Value	200
Comment	For Profile position mode 6060h=1 Unit: millisecond (time from 0rpm to 3000rpm)

Object 6084h: Profile deceleration

INDEX	6084h
Name	Profile deceleration
Object Code	VAR
Data Type	UNSIGNED32
Access	RW
PDO Mapping	Yes
Value Range	1~UNSIGNED32
Default Value	200
Comment	For Profile position mode 6060h=1 Unit: millisecond (time from 0rpm to 3000rpm)

Object 6085h: Quick stop deceleration

INDEX	6085h
Name	Quick stop acceleration
Object Code	VAR
Data Type	UNSIGNED32
Access	RW

PDO Mapping	Yes
Value Range	UNSIGNED32
Default Value	0
Comment	Unit: millisecond (time from 0rpm to 3000rpm)

Object 6086_h: Motion profile type

INDEX	6086 _h
Name	Motion profile type
Object Code	VAR
Data Type	INTEGER16
Access	RW
PDO Mapping	Yes
Value Range	INTEGER16
Default Value	0

Object 6087_h: Torque slope

INDEX	6087 _h
Name	Torque slope
Object Code	VAR
Data Type	UNSIGNED32
Access	RW
PDO Mapping	Yes
Value Range	UNSIGNED32
Default Value	0
Comment	Unit: millisecond (time from 0 to 100% rated torque)

Object 6093_h: Position factor

INDEX	6093 _h
Name	Position factor
Object Code	ARRAY
Data Type	UNSIGNED32
Access	RW
PDO Mapping	Yes

Comment	Position factor = Numerator / Feed_constant
---------	--

Sub-Index	0
Description	Number of entries
Data Type	UNSIGNED8
Access	RO
PDO Mapping	No
Value Range	2
Default Value	2

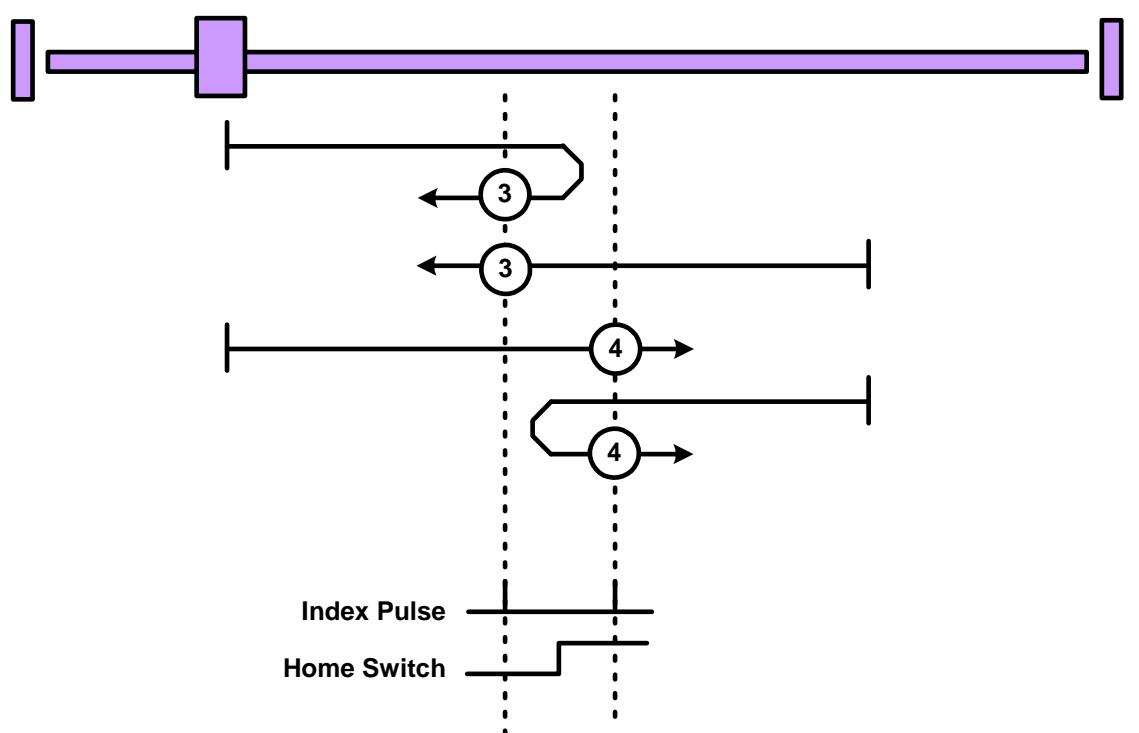
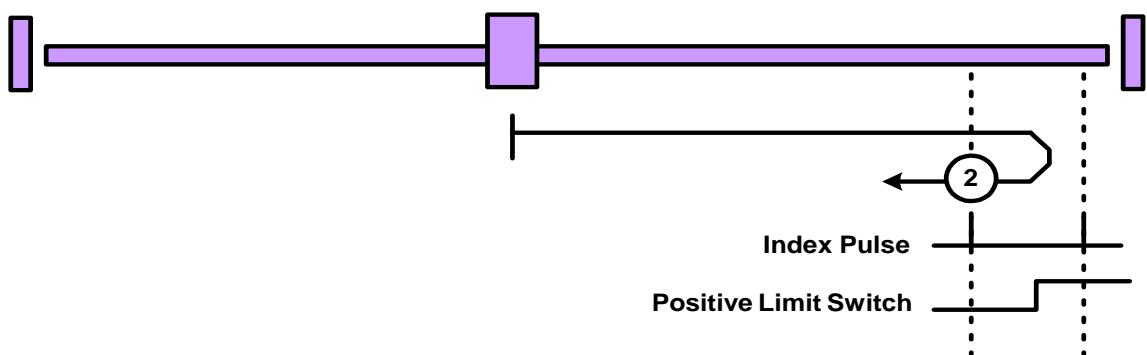
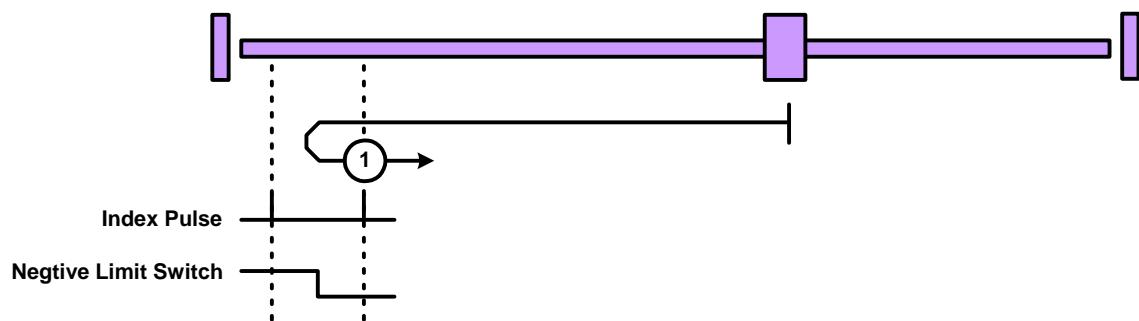
Sub-Index	1
Description	Numerator
Data Type	UNSIGNED32
Access	RW
PDO Mapping	Yes
Default Value	1
Comment	Same as P1-44

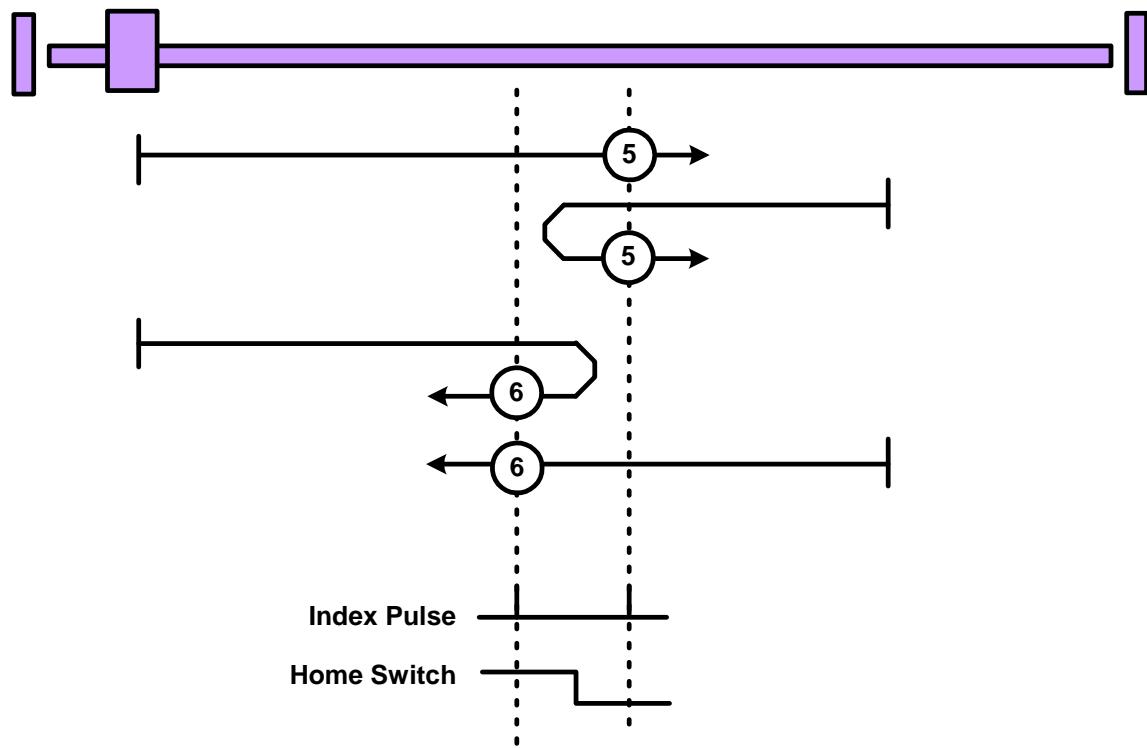
Sub-Index	2
Description	Feed_constant
Data Type	UNSIGNED32
Access	RW
PDO Mapping	Yes
Default Value	1
Comment	Same as P1-45

Object 6098_h: Homing method

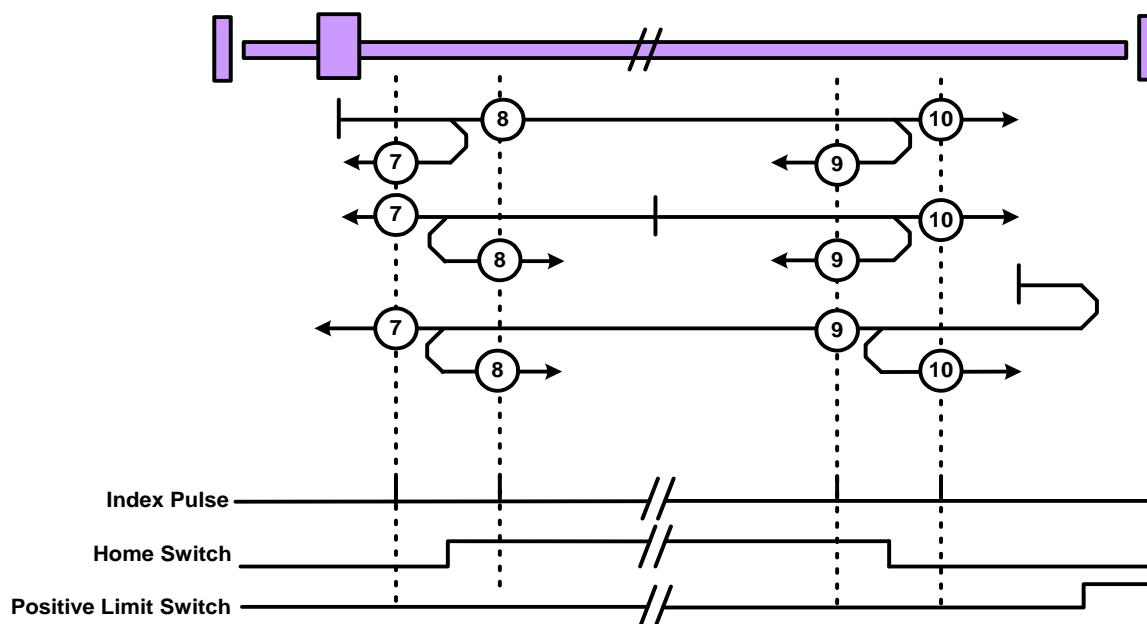
INDEX	6098 _h
Name	Homing method
Object Code	VAR
Data Type	INTEGER8
Access	RW
PDO Mapping	Yes
Value Range	0~35

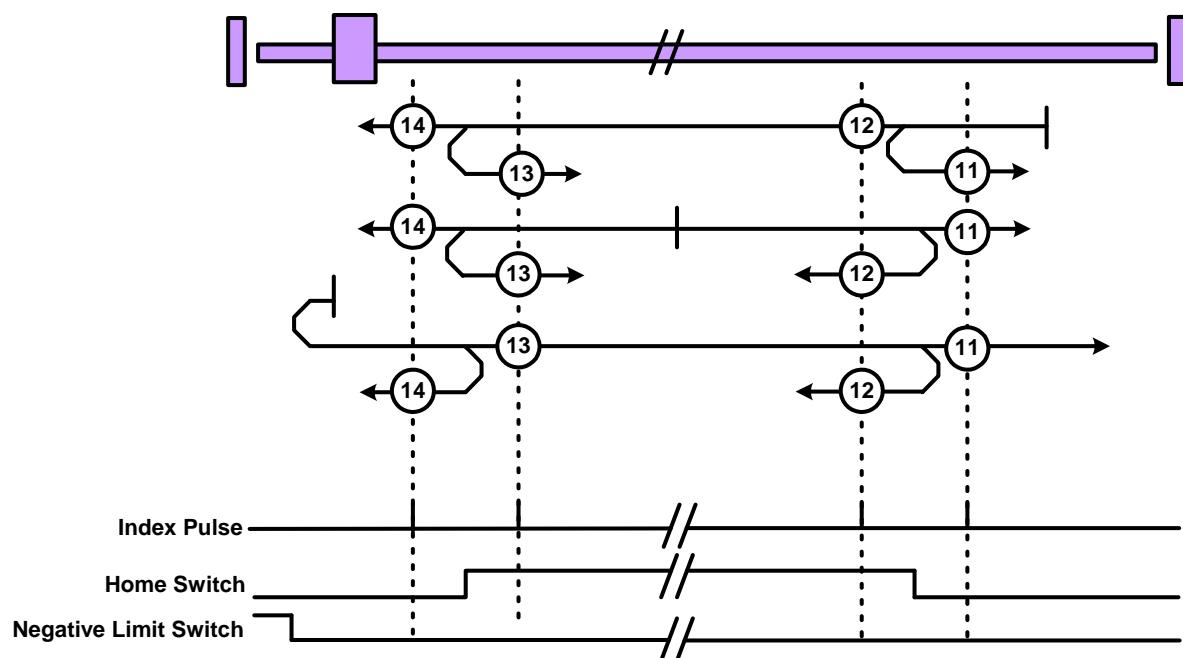
Default Value	0
---------------	---





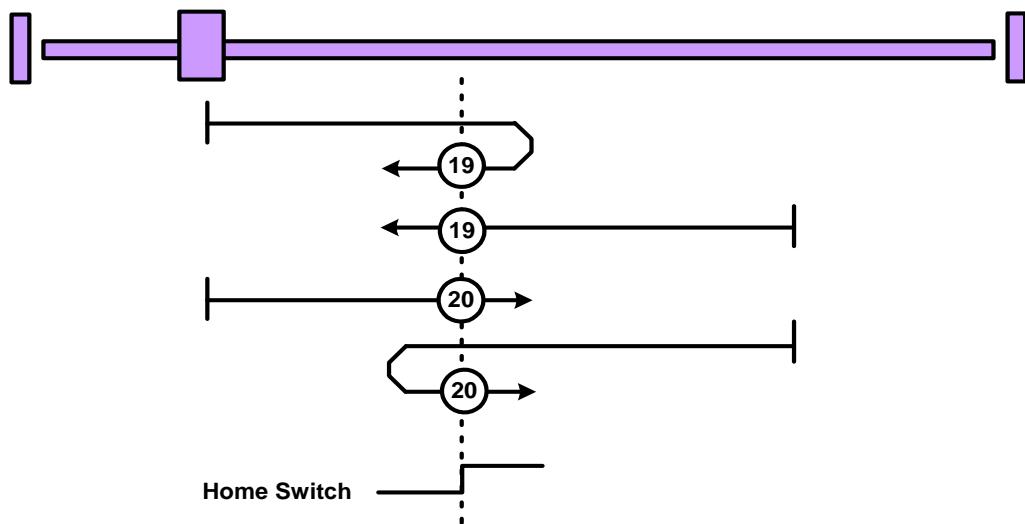
Method 5 and 6 : Homing on negative home switch and index pulse





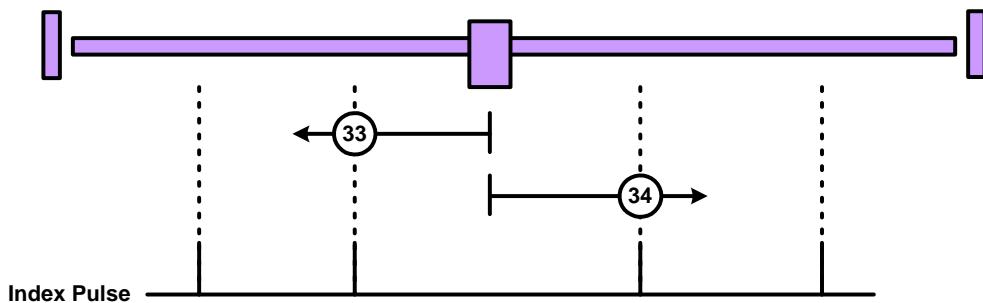
Method 7 to 14 : Homing on home switch and index pulse

Method 15 and 16 : Reserved (no picture)



Method 17 to 30 : Homing without an index pulse

Method 31 and 32 : Reserved (no picture)



Method 33 to 34 : Homing on index pulse

Method 35 : Homing on current position (no picture)

Object 6099_h: Homing speed

INDEX	6099 _h
Name	Homing speed
Object Code	ARRAY
Data Type	UNSIGNED32
Access	RW
PDO Mapping	Yes

Sub-Index	0
Description	Number of entries
Data Type	UNSIGNED8
Access	RO
PDO Mapping	Yes
Value Range	2
Default Value	2
Sub-Index	1
Description	Speed during search for switch
Data Type	UNSIGNED32
Access	RW
PDO Mapping	Yes
Value Range	1~2000rpm
Default Value	100
Comment	Unit:0.1rpm

Sub-Index	2
Description	Speed during search for zero
Data Type	UNSIGNED32
Access	RW
PDO Mapping	Yes
Value Range	1~500rpm

Default Value	20
Comment	Unit:0.1rpm

Object 609A_h: Homing acceleration

INDEX	609A _h
Name	Homing acceleration
Object Code	VAR
Data Type	UNSIGNED32
Access	RW
PDO Mapping	Yes
Value Range	UNSIGNED32
Default Value	100
Comment	Unit: millisecond (time of acc from 0rpm to 3000rpm)

Object 60B0_h: Position offset

INDEX	60B0 _h
Name	Position offset
Object Code	VAR
Data Type	INTEGER32
Access	RW
PDO Mapping	Yes
Value Range	INTEGER32
Default Value	0
Comment	Unit: PUU

Object 60B1_h: Velocity offset

INDEX	60B1 _h
Name	Velocity offset
Object Code	VAR
Data Type	INTEGER32
Access	RW
PDO Mapping	Yes
Value Range	INTEGER32

Default Value	0
Comment	Unit: 0.1rpm

Object 60B2_h: Torque offset

INDEX	60B2 _h
Name	Torque offset
Object Code	VAR
Data Type	INTEGER16
Access	RW
PDO Mapping	Yes
Value Range	3000~-3000
Default Value	0
Comment	Unit: one rated torque in a thousand

Object 60B8_h: Touch probe function

INDEX	60B8 _h
Name	Touch probe function
Object Code	VAR
Data Type	UNSIGNED16
Access	RW
PDO Mapping	Yes
Value Range	UNSIGNED16
Default Value	0
Comment	0

Object 60B9_h: Touch probe status

INDEX	60B9 _h
Name	Touch probe status
Object Code	VAR
Data Type	UNSIGNED16
Access	RO
PDO Mapping	Yes
Value Range	UNSIGNED16

Default Value	0
Comment	0

Object 60BA_h: Touch probe pos1 pos value

INDEX	60BA _h
Name	Touch probe pos1 pos value
Object Code	VAR
Data Type	INTEGER32
Access	RO
PDO Mapping	Yes
Value Range	INTEGER32
Default Value	0
Comment	Unit: PUU

Object 60BB_h: Touch probe pos1 neg value

INDEX	60BB _h
Name	Touch probe pos1 neg value
Object Code	VAR
Data Type	INTEGER32
Access	RO
PDO Mapping	Yes
Value Range	INTEGER32
Default Value	0
Comment	Unit: PUU

Object 60BC_h: Touch probe pos2 pos value

INDEX	60BC _h
Name	Touch probe pos2 pos value
Object Code	VAR
Data Type	INTEGER32
Access	RO
PDO Mapping	Yes
Value Range	INTEGER32
Default Value	0

Comment	Unit: PUU
---------	-----------

Object 60BD_h: Touch probe pos2 neg value

INDEX	60BD _h
Name	Touch probe pos2 neg value
Object Code	VAR
Data Type	INTEGER32
Access	RO
PDO Mapping	Yes
Value Range	INTEGER32
Default Value	0
Comment	Unit: PUU

Object 60C0_h: Interpolation sub mode select

INDEX	60C0 _h
Name	Interpolation sub mode select
Object Code	VAR
Data Type	INTEGER16
Access	RW
PDO Mapping	Yes
Value Range	INTEGER16
Default Value	0
Comment	0: manufacturer specific (Linear interpolation -- no need the Pos Difference [OD- 60C1sub2]) -1: manufacturer specific (Delta definition -- need pos difference [OD-60C1sub2])

Object 60C1_h: Interpolation data record

INDEX	60C1 _h
Name	Interpolation data record
Object Code	ARRAY
Data Type	INTEGER32
Access	RW
PDO Mapping	Yes
Comment	Set this record by PDO every T msec before SYNC message Where T is specified by 60C2 _h :01 _h

Sub-Index	0
Description	Number of entries
Data Type	UNSIGNED8
Access	RO
PDO Mapping	No
Value Range	2
Default Value	2

Sub-Index	1
Description	Pos_Cmd
Data Type	INTEGER32
Access	RW
PDO Mapping	Yes
Value Range	INTEGER32
Default Value	0
Comment	Unit: 32-bit CMD_PUU
Sub-Index	2
Description	Velocity – Pos_Cmd difference
Data Type	INTEGER16
Access	RW
PDO Mapping	Yes
Value Range	INTEGER16
Default Value	0
Comment	$\Delta X_i = (X_{i+1} - X_{i-1})/2$ (It is also the same as velocity.)

Unit: PUU

Object 60C2_h: Interpolation time period

INDEX	60C2 _h
Name	Interpolation time period
Object Code	RECORD
Data Type	UNSIGNED8
Access	RW
PDO Mapping	Yes
Comment	The unit of the interpolation time unit is given in 10 ^{interpolation time index} seconds

Sub-Index	0
Description	Number of entries
Data Type	UNSIGNED8
Access	RO
PDO Mapping	No
Value Range	2
Default Value	2

Sub-Index	1
Description	Interpolation time units
Data Type	UNSIGNED8
Access	RW
PDO Mapping	Yes
Value Range	UNSIGNED8
Default Value	1

Sub-Index	2
Description	Interpolation time index
Data Type	INTEGER8
Access	RW
PDO Mapping	Yes
Value Range	-128~63
Default Value	-3

Object 60C5_h: Max acceleration

INDEX	60C5 _h
Name	Max acceleration
Object Code	VAR
Data Type	UNSIGNED32
Access	RW
PDO Mapping	Yes
Value Range	UNSIGNED32
Default Value	200

Object 60C6_h: Max deceleration

INDEX	60C6 _h
Name	Max deceleration
Object Code	VAR
Data Type	UNSIGNED32
Access	RW
PDO Mapping	Yes
Value Range	UNSIGNED32
Default Value	200

Object 60F2_h: Positioning option code

INDEX	60F2 _h
Name	Positioning option code
Object Code	VAR
Data Type	UNSIGNED16
Access	RW
PDO Mapping	Yes
Value Range	UNSIGNED16
Default Value	0

Object 60F4_h: Following error actual value

INDEX	60F4 _h
Name	Following error actual value
Object Code	VAR
Data Type	INTEGER32
Access	RO
PDO Mapping	Yes
Value Range	INTEGER32
Comment	Unit: PUU

Object 60FC_h: Position demand value*

INDEX	60FC _h
Name	Position demand value*
Object Code	VAR
Data Type	INTEGER32
Access	RO
PDO Mapping	Yes
Value Range	INTEGER32
Comment	Unit: increment

Object 60FD_h: Digital inputs

INDEX	60FD _h
Name	Digital inputs
Object Code	VAR
Data Type	UNSIGNED32
Access	RO
PDO Mapping	Yes
Value Range	UNSIGNED32
Default Value	0

31	3	2	1	0
reserved	home switch	positive limit switch	negative limit switch	
MSB				LSB

Object 60FF_h: Target velocity

INDEX	60FF _h
Name	Target velocity
Object Code	VAR
Data Type	INTEGER32
Access	RW
PDO Mapping	Yes
Value Range	INTEGER32
Comment	Unit: 0.1rpm

Object 6502_h: Supported drive modes

INDEX	6502 _h
Name	Supported drive modes
Object Code	VAR
Data Type	UNSIGNED32
Access	Ro
PDO Mapping	Yes
Value Range	UNSIGNED32
Default Value	3ED _h

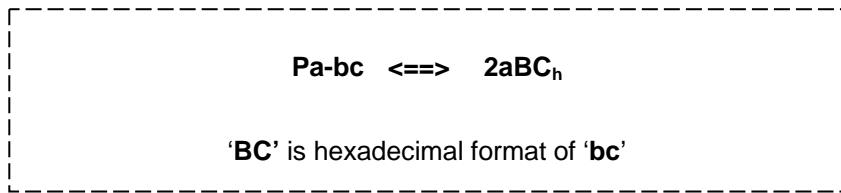
31	16	15	7	6	5	4	3	2	1	0
Manufacturer specific		reserved	ip	hm	reserved	tq	pv	vl	pp	
MSB										LSB

Object 2xxx_h: Manufacturer parameter

INDEX	2xxx _h
Name	Manufacturer parameter
Object Code	VAR
Data Type	INTEGER16/INTEGER32
Access	RW
PDO Mapping	Yes
Value Range	INTEGER16/INTEGER32
Default Value	N/A

Object 2xxx is defined to parameter.

If users desire to use CANopen protocol for simulate Keypad press, they could read and write Keypad parameters via SDO protocol.



Users could read the Index first for knowing the Length of Parameter and then change the data by SDO or PDO.

Example 1: Object 2309_h: EtherCAT Synchronization Setting 【P3-09】

INDEX	2309 _h
Name	EtherCAT Synchronization Setting
Object Code	VAR
Data Type	INTEGER16
Access	RW
PDO Mapping	Yes
Value Range	INTEGER16
Default Value	1512 _h

Example 2: Object 212C_h: Electronic Gear 【P1-44】

INDEX	212C _h
Name	Electronic Gear
Object Code	VAR
Data Type	INTEGER32
Access	RW
PDO Mapping	Yes
Value Range	INTEGER32

Chapter 7 Alarm List

7.1 EtherCAT Communication Fault Messages

Emergency Object

Byte	0	1	2	3	4	5	6	7
Content	Emergency Error Code	Error register	Panel Alarm	Code		N/A		

Fault Messages

(If ALARM code is not showed here, please refer to the User Manual)

Display	Fault Name	Fault Description	Clearing Method
AL185	Communication disconnected	EtherCAT link is disconnected	6040h fault reset
AL170	Node guarding or Heartbeat error (Servo On)	Error about node guarding or heartbeat of CANopen protocol	6040h fault reset
AL180	Node guarding or Heartbeat error (Servo Off)	Error about node guarding or heartbeat of CANopen protocol	6040h fault reset
AL111	CANopen SDO receives buffer overflow	SDO Rx buffer overflow is detected (receive two or more SDO packets in 1ms).	6040h fault reset
AL112	CANopen PDO receives buffer overflow	PDO Rx buffer overflow is detected (receive two or more PDO (same COBID) packets in 1ms).	6040h fault reset
AL121	Index error occurs when accessing CANopen PDO object.	The specified Index in the message does not exist.	6040h fault reset

AL122	Sub-index error occurs when accessing CANopen PDO object.	The specified Sub-index in the message does not exist.	6040h fault reset
AL123	Data type (size) error occurs when accessing CANopen PDO object.	The data length in the message does not match the specified object.	6040h fault reset
AL124	Data range error occurs when accessing CANopen PDO object.	The data in the message has exceeded the data range of the specified object.	6040h fault reset
AL125	CANopen PDO object is read-only and write-protected.	The specified object in the message is read-only and write-protected (cannot be changed).	6040h fault reset
AL126	CANopen PDO object does not support PDO.	The specified object in the message does not support PDO.	6040h fault reset
AL127	CANopen PDO object is write-protected when Servo On.	The specified object in the message is write-protected (cannot be changed) when Servo On.	6040h fault reset
AL128	Error occurs when reading CANopen PDO object from EEPROM.	An error occurs when loading the default settings from EEPROM at start-up. All CANopen object returns to the default setting automatically.	6040h fault reset
AL129	Error occurs when writing CANopen PDO object into EEPROM.	An error occurs when writing the current settings into EEPROM.	6040h fault reset

AL130	EEPROM invalid address range	The data amount saved in EEPROM has exceeded the space determined by the firmware. Maybe the firmware version has been upgraded, and the data of old firmware version saved in EEPROM cannot be used.	6040h fault reset
AL131	EEPROM checksum error	The data saved in EEPROM has been damaged and all CANopen objects return to the default settings automatically.	6040h fault reset
AL132	Password error	The parameter is password protected when using CANopen communication to access the parameter. The users must enter the valid password to unlock the parameter.	6040h fault reset
AL201	CANopen load/save 1010/1011 error	Fail while read/write data from/to EEPROM	P2-08 = 10 or P2-08 = 30,28 after firmware upgrade
AL301	CANopen SYNC failed (Servo On)	The synchronous communication with the external controller has failed.	6040h fault reset
AL302	CANopen SYNC signal error (Servo On)	The CANopen SYNC signal is received too early.	6040h fault reset
AL303	CANopen SYNC time out (Servo On)	The CANopen SYNC signal is not received within the specified time.	6040h fault reset
AL304	CANopen IP command failed (Servo On)	Internal command of CANopen IP mode cannot be sent and received.	6040h fault reset
AL305	SYNC period error (Servo On)	Object 0x1006 data error. SYNC period 1006h value is invalid.	6040h fault reset
AL3E1	CANopen SYNC failed (Servo Off)	The synchronous communication with the external controller has failed.	6040h fault reset

AL3E2	CANopen SYNC signal error (Servo Off)	The CANopen SYNC signal is received too early.	6040h fault reset
AL3E3	CANopen SYNC time out (Servo Off)	The CANopen SYNC signal is not received within the specified time.	6040h fault reset
AL3E4	CANopen IP command failed (Servo Off)	Internal command of CANopen IP mode cannot be sent and received.	6040h fault reset
AL3E5	SYNC period error (Servo Off)	Object 0x1006 data error. SYNC period 1006h value is invalid.	6040h fault reset
AL401	CANopen state error	NMT reset or NMT stop is received when the drive is enabled	6040h fault reset
AL500	Safe torque off (Servo Off)	The safety function STO is activated. STO_A and STO_B change state simultaneously.	6040h fault reset
AL501	STO_A lost (Servo Off)	STO_A is de-energized and STO_B is energized. The level of STO_A and STO_B are different for more than 1 second, please check wiring contact or STO safety relay.	6040h fault reset
AL502	STO_B lost (Servo Off)	STO_A is energized and STO_B is de-energized. The level of STO_A and STO_B are different for more than 1 second, please check wiring contact or STO safety relay.	6040h fault reset
AL503	STO error (Servo Off)	STO self-diagnostic error	6040h fault reset

7.2 Error Code Table

Display	Description	32bit-ErrorCode (16bit-ErrorCode + 16bit-Additional Info)
AL001	Overcurrent	2310-0001 _h
AL002	Overvoltage	3110-0002 _h
AL003	Undervoltage	3120-0003 _h
AL004	Motor error	7122-0004 _h
AL005	Regeneration error	3210-0005 _h
AL006	Overload	3230-0006 _h
AL007	Overspeed	8400-0007 _h
AL008	Abnormal pulse control command	8600-0008 _h
AL009	Excessive deviation	8611-0009 _h
AL010	Reserved	0000-0010 _h
AL011	Encoder error	7305-0011 _h
AL012	Adjustment error	6320-0012 _h
AL013	Emergency stop activated	5441-0013 _h
AL014	Reverse limit switch error	5443-0014 _h
AL015	Forward limit switch error	5442-0015 _h
AL016	IGBT temperature error	4210-0016 _h
AL017	Memory error	5330-0017 _h
AL018	Encoder output error	7306-0018 _h
AL019	Serial communication error	7510-0019 _h
AL020	Serial communication time out	7520-0020 _h
AL021	Reserved	Reserved
AL022	Input power phase loss	3130-0022 _h
AL023	Early warning for overload	3231-0023 _h
AL024	Encoder initial magnetic field error	7305-0024 _h
AL025	Encoder internal error	7305-0025 _h
AL026	Encoder internal error	7305-0026 _h

AL027	Encoder data error	7305-0027 _h
AL030	Motor protection error	7121-0030 _h
AL031	U,V,W wiring error	3300-0031 _h
AL040	Full-closed loop excessive deviation	8610-0040 _h
AL099	DSP firmware upgrade	5500-0099 _h
AL201	CANopen Data Initial Error	6310-0201 _h
AL283	Forward software limit	5444-0283 _h
AL285	Reverse software limit	5445-0285 _h
AL185	EtherCAT connection error (Servo Off)	8120-0185 _h
AL170	Node guarding or Heartbeat error (Servo On)	8130-0170 _h
AL180	Node guarding or Heartbeat error (Servo Off)	8130-0180 _h
AL111	CANopen SDO receive buffer overflow	8110-0111 _h
AL112	CANopen PDO receive buffer overflow	8110-0112 _h
AL121	Index error occurs when accessing CANopen PDO object.	8200-0121 _h
AL122	Sub-index error occurs when accessing CANopen PDO object.	8200-0122 _h
AL123	Data type (size) error occurs when accessing CANopen PDO object.	8200-0123 _h
AL124	Data range error occurs when accessing CANopen PDO object.	8200-0124 _h
AL125	CANopen PDO object is read-only and write-protected.	8200-0125 _h
AL126	CANopen PDO object does not support PDO.	8200-0126 _h
AL127	CANopen PDO object is write-protected when Servo On.	8200-0127 _h
AL128	Error occurs when reading CANopen PDO object from EEPROM.	8200-0128 _h
AL129	Error occurs when writing CANopen PDO object into EEPROM.	8200-0129 _h

AL130	EEPROM invalid address range.	8200-0130 _h
AL131	EEPROM checksum error.	8200-0131 _h
AL132	EEPROM zone error.	8200-0132 _h
AL201	CANopen load/save 1010/1011 error	6310-0201 _h
AL3E1	CANopen SYNC failed (Servo Off)	6200-03E1 _h
AL3E2	CANopen SYNC signal error (Servo Off)	6200-03E2 _h
AL3E3	CANopen SYNC time out (Servo Off)	6200-03E3 _h
AL3E4	CANopen IP command failed (Servo Off)	6200-03E4 _h
AL3E5	SYNC period error (Servo Off)	6200-03E5 _h
AL401	CANopen state error	8100-0401 _h
AL500	Safe torque off (Servo Off)	9000-0500 _h
AL501	STO_A lost (Servo Off)	9000-0501 _h
AL502	STO_B lost (Servo Off)	9000-0502 _h
AL503	STO error (Servo Off)	9000-0503 _h

7.3 SDO Error Message Abort Codes

Abort Code	Description
05040001 _h	Client/server command specifier not valid or unknown
06010002 _h	Attempt to write a read-only object
06020000 _h	Object does not exist in the object dictionary
06040041 _h	Object cannot be mapped to PDO
06040042 _h	The number and the length of the objects to be mapped would exceed PDO length
06060000 _h	Access failed due to a hardware error (store or restore error)
06070010 _h	Data type does not match; length of the service parameter does not match
06090011 _h	Sub-index does not exist
06090030 _h	Value range of parameter exceeded (only for writing access)
08000000 _h	General error
080000a1 _h	Object error when reading from EEPROM
080000a2 _h	Object error when writing to EEPROM
080000a3 _h	Invalid Range when accessing EEPROM
080000a4 _h	Checksum error when accessing EEPROM
080000a5 _h	Password error when writing encryption zone
08000020 _h	Data cannot be transferred or stored in the application (store or restore signature error)
08000021 _h	Data cannot be transferred or stored in the application because of the local control (store or restore in wrong state)
08000022 _h	Object is on the fly

Chapter 8 Reference

1. CANopen Application Layer and Communication Profile, CiA Draft Standard 301, Version 4.02, Date: 13 February 2002
2. CANopen Device Profile Drives and Motion Control, CiA Draft Standard Proposal 402, Version 2.0, Date: 26 July 2002

(This page is intentionally left blank.)